Start using ROS with Pepper

Install ros
http://wiki.ros.org/ROS/Installation
Make sure to install Kinetic

Install Python Naoqi SDK, need regist
Download and unzip the file to naoqi folder
In your home directory
mkdir naoqi
Download: https://community.ald.softbankrobotics.com/en/resources/software/language/en-gb

Edit .bashrc file, include following line
export export PYTHONPATH=$HOME/naoqi/pynaoqi-python2.7-2.5.5.5-linux64/lib/python2.7/site-packages:$PYTHONPATH
export PYTHONPATH=$HOME/naoqi/pynaoqi-python2.7-2.5.5.5-linux64:$PYTHONPATH

Pepper tutorial
There is a chance that this will not work, if not work see the jsk_naoqi_robot instruction
http://wiki.ros.org/pepper/Tutorial_kinetic

Rviz and pepper pre-config file
rosrun rviz rviz
Locate pepper pre-config file
on the rviz panal, file->open config
the pre config file for pepper is under, you can copy this file and paste in the place you like
/opt/ros/kinetic/share/pepper_bringup/config

jsk_naoqi_robot

jsk ros packages are created by The University of Tokyo, they are open sources. jsk_naoqi_robot is the package desined for both NAO and Pepper. Simply follow the instruction in the link below. But before doing that, there are some steps need to be made.
Install catkin-tool
jsk packages are normally used with catkin build command to build the enviroment and packages, therefore catkin-tool need to be installed inorder to run the catkin build command.
sudo apt-get install python-catkin-tools
catkin-tool references
https://catkin-tools.readthedocs.io/en/latest/cheat_sheet.html
Reconfig work space
Next step is to setup the work space, you can remove the build and devel folder from the workspace created ealier that were build by catkin_make, or you can create a new workspace.
The instruction will remove the build and devel folder from workspace builted by catkin_make

Initialise workspace extends to another workspace
catkin config --init --extend /opt/ros/kinetic
build workspace
catkin build

Now follow the jsk_naoqi_robot instruction
https://github.com/jsk-ros-pkg/jsk_robot/tree/master/jsk_naoqi_robot
In case not find naoqi_node.py under the directory, the code file can be locate at, copy the code to the directory needed.
http://docs.ros.org/jade/api/naoqi_driver_py/html/naoqi__node_8py_source.html

Modify pepper_bringup launch file in order to get it work

cd /opt/ros/kinetic/share/pepper_bringup/launch

edit the pepper_full.launch file as described in https://github.com/ros-naoqi/pepper_robot/pull/40/files

Launch pepper_bringup

roslaunch pepper_bringup pepper_full.launch networ_interface:=enp2s0 roscore_ip:=kate-iMac.local

roscore_ip can be found by running roscore command, see the ROS_MASTER_URI