Differential Drive Robot

Midterm Task – Setup Documentation

Submitted by:

Abdelhamid Walid Abdelhamid [1190463]

Abdelrahman Adel Ramadan [1190140]

Mostafa Mohamed Mahmoud Shafik [1190485]

Mohamed Adel Hamzawi [1190500]

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Submitted to: Dr. Hossam Ammar

1 – Initializing ROS Master

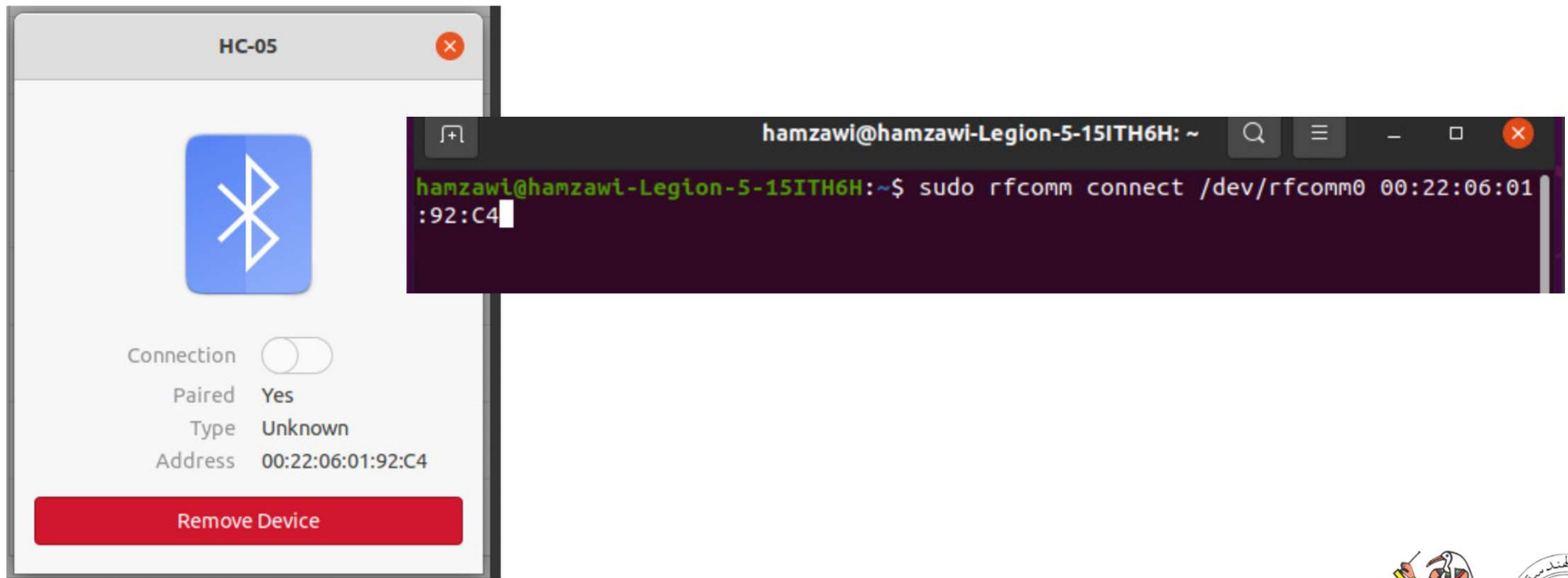## 2 – Running rosserial for Joystick Arduino Node via USB Port
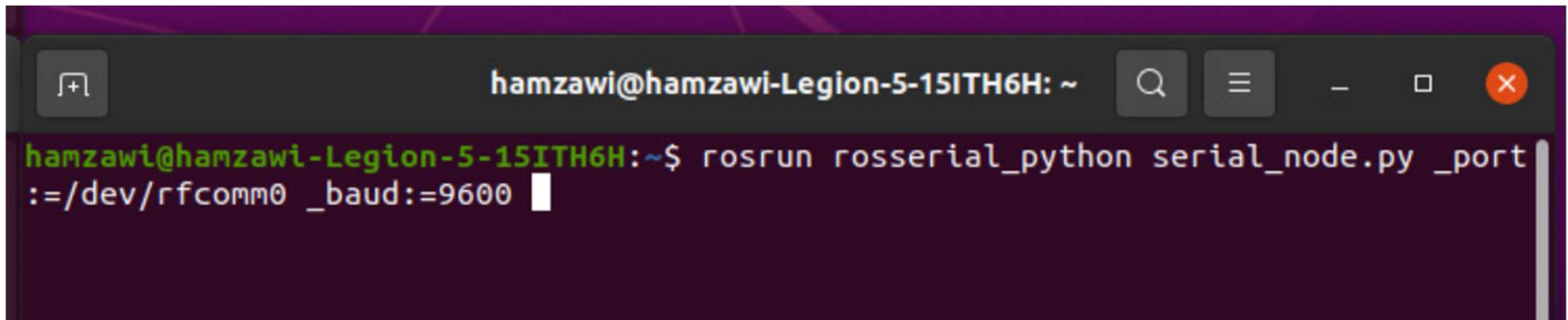


```
hamzawi@hamzawi-Legion-5-15ITH6H:~$ rosrun rosserial_python serial_node.py _port
:=/dev/ttyUSB0 _baud:=9600 __name:=nano
```

3 – Connecting Bluetooth module with ROS by configuring it as serial port
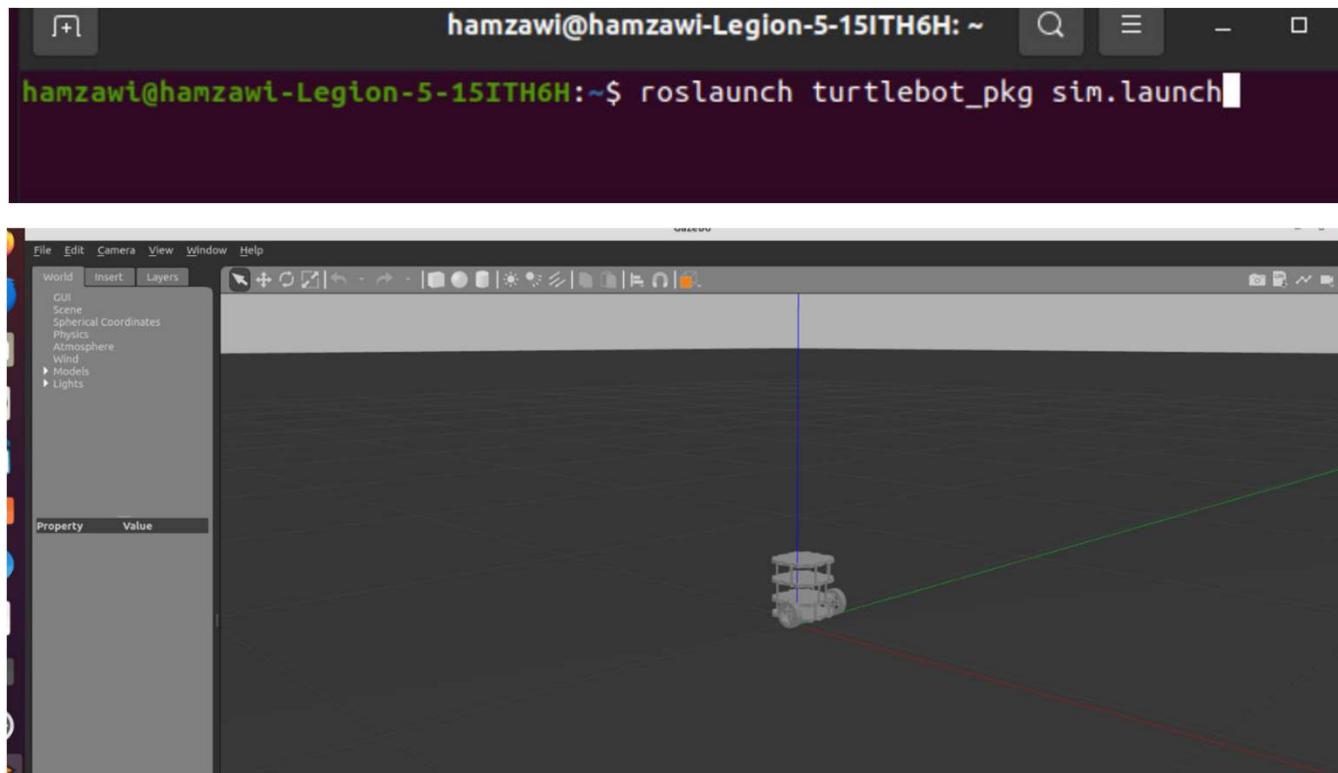
4 – Running rosserial for Robot Arduino Node using serial port (Bluetooth configured)
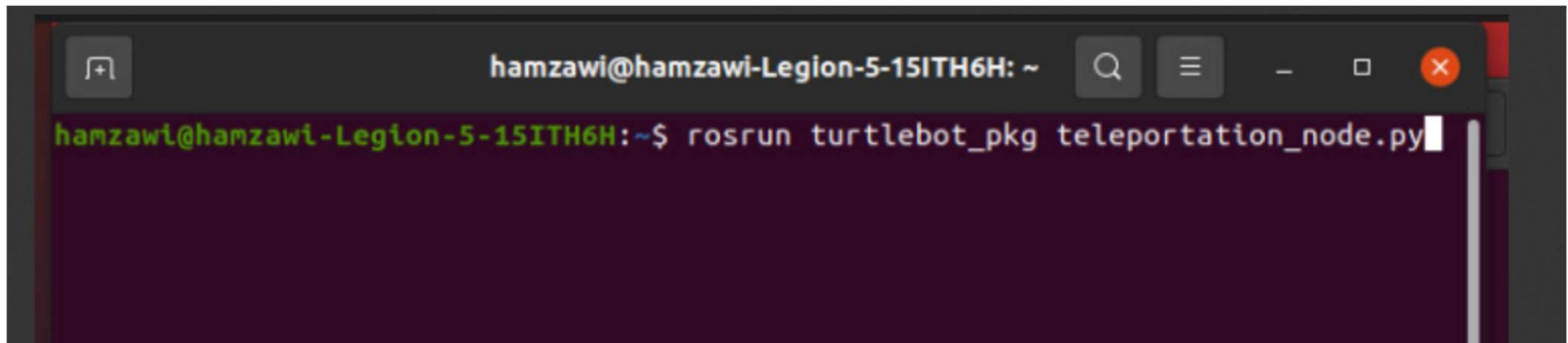


```
hamzawi@hamzawi-Legion-5-15ITH6H:~$ rosrun rosserial_python serial_node.py _port
:=/dev/rfcomm0 _baud:=9600
```

5 – Running the Gazebo file using the launch file

6 – Running rosrun for the main node "teleportation_node.py"