تثبيت وتشغيل باكج الذراع على نظام ROS

1. تثبيت نظام ROS
2. نروح لموجة الأوامر ونكتب :
3. rosdep update
4. sudo apt-get install ros-noetic-catkin
5. mkdir -p ~/catkin\_ws/src
6. cd ~/catkin\_ws/
7. catkin\_make
8. cd ~/catkin\_ws/src
9. git clone https://github.com/smart-methods/arduino\_robot\_arm.git
10. cd ~/catkin\_ws
11. rosdep install --from-paths src --ignore-src -r -y
12. sudo apt-get install ros-kinetic-moveit
13. sudo apt-get install ros-kinetic-joint-state-publisher ros-kinetic-joint-state-publisher-gui
14. sudo apt-get install ros-kinetic-gazebo-ros-control joint-state-publisher
15. sudo apt-get install ros-kinetic-ros-controllers ros-kinetic-ros-control
16. sudo nano ~/.bashrc
17. at the end of the (bashrc) file add the follwing line
18. (source /home/اسم النظام/catkin\_ws/devel/setup.bash)
19. then
20. ctrl + o
21. source ~/.bashrc
22. roslaunch robot\_arm\_pkg check\_motors.launch

