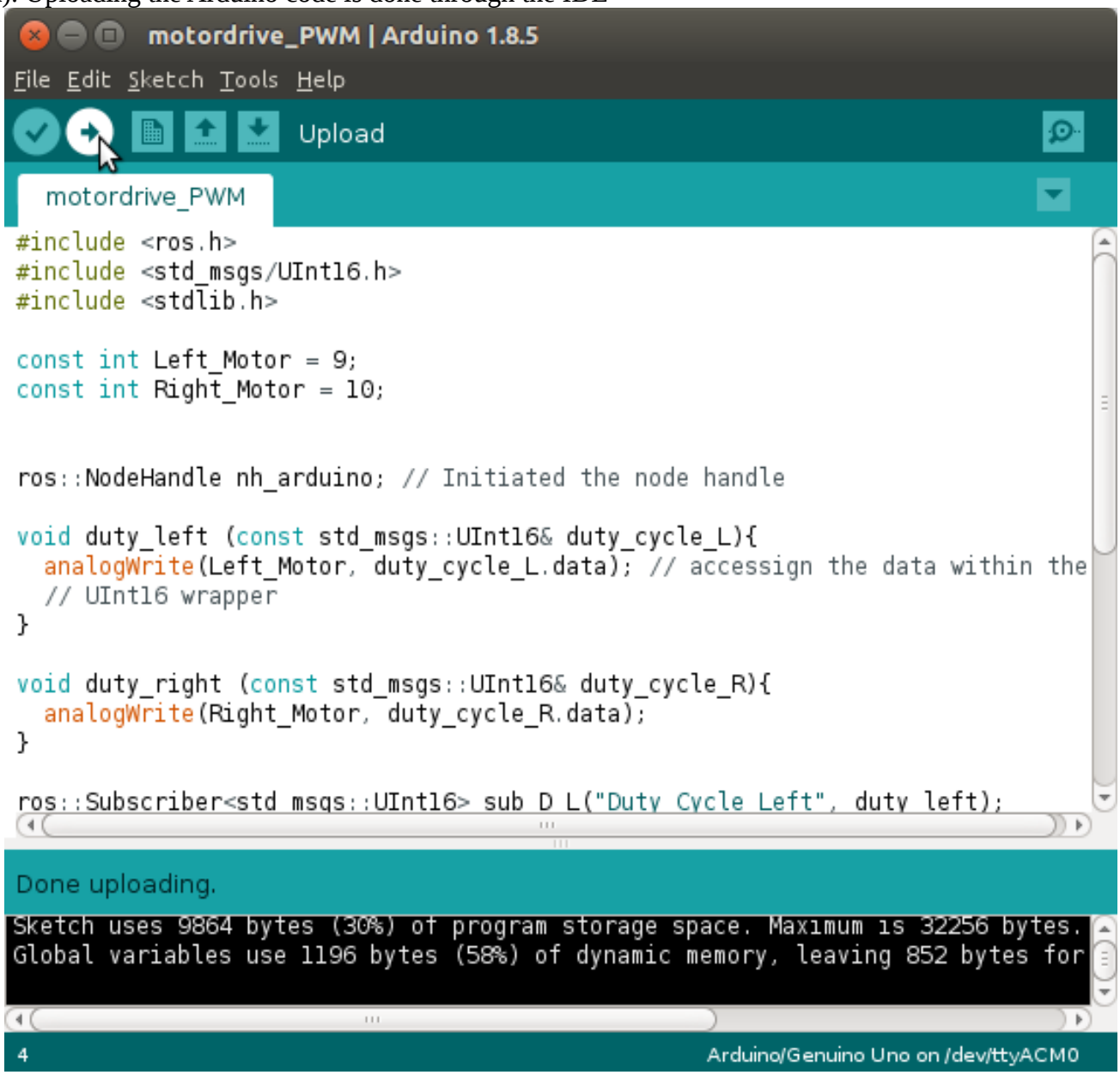
Steps:
1. Load Arduinio Code onto board
2. Start ROS nodes

Step 1:
a). Uploading the Arduino code is done through the IDE

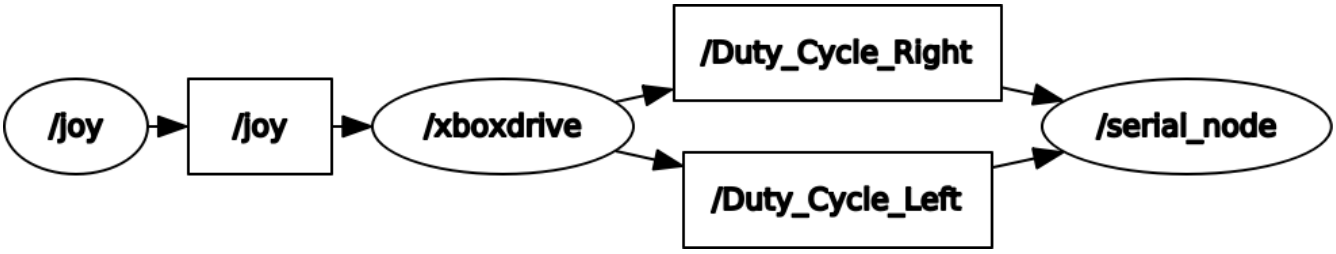


b). Make sure that Arduino is connected to the computer through a USB port

Step 2.:
a) Execute the following commands in this order

```
utcr2018@utcr2018-OptiPlex-3010:~$ cd catkin_ws/
utcr2018@utcr2018-OptiPlex-3010:~/catkin_ws$ source devel/setup.bash
utcr2018@utcr2018-OptiPlex-3010:~/catkin_ws$ roslaunch motordrive Joystick_Drive.launch
ex-3010-875.log
Checking log directory for disk usage. This may take awhile.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://utcr2018-OptiPlex-3010:35951/

SUMMARY
========

PARAMETERS
 * /rosdistro: kinetic
 * /rosversion: 1.12.13
 * /serial_node/baud: 57600
 * /serial_node/port: /dev/ttyACM0

NODES
  /
    joy (joy/joy_node)
    serial_node (rosserial_python/serial_node.py)
    xboxdrive (motordrive/xboxdrive)

auto-starting new master
process[master]: started with pid [889]
ROS_MASTER_URI=http://localhost:11311
```

b) your rqt_graph should look like this:
Execute the command ‘rqt_graph’ in a separate terminal window



Driving the robot:
1) pushing A starts the robot – green light will turn on
2) left stick will move forwards and backwards
3) right stick will steer like a jet ski – must be moving under power to steer

If the Arduino does not connect, try roslaunch motordrive Joystick_Drive.launch port:=/dev/tty/ACMX where X is 1,2,3,4….