myCobotRos教程

1. Install ROS

```
# set source.lis
sudo sh -c 'echo "deb http://packages.ros.org/ros/ubuntu $(lsb_release -sc) main" > /etc/apt/sources.list.d/ros-latest.list'

# add key
sudo apt-key adv --keyserver 'hkp://keyserver.ubuntu.com:80' --recv-key C1CF6E31E6BADE8868B172B4F42ED6FBAB17C654

# update software
sudo apt-get update
# install ros
sudo apt-get install ros-kinetic-desktop-full

# inital ros
sudo rosdep init
rosdep update

# set ros env
echo "source /opt/ros/kinetic/setup.bash" >> ~/.bashrc
source ~/.bashrc

# install ros dependency packages
sudo apt-get install python-rosinstall python-rosinstall-generator python-wstool build-essential

# test wether install success
roscore
```

```
roscore http://ThundeRobot:11311/
zhenkai@ThundeRobot:~$ roscore
... logging to /home/zhenkai/.ros/log/17f0fab4-d7fe-11e8-b1f8-b46d83d664c9/roslaunch-ThundeRobot-25254.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://ThundeRobot:38281/
ros_comm version 1.12.14


SUMMARY
========

PARAMETERS
 * /rosdistro: kinetic
 * /rosversion: 1.12.14

NODES

auto-starting new master
process[master]: started with pid [25265]
ROS_MASTER_URI=http://ThundeRobot:11311/

setting /run_id to 17f0fab4-d7fe-11e8-b1f8-b46d83d664c9
process[rosout-1]: started with pid [25278]
started core service [/rosout]
```

2. Create ROS workspace

```
$ mkdir -p ~/catkin_ws/src
$ cd ~/catkin_ws/
$ catkin_make
```

If you want to use python3, the first catkin_make command in a clean catkin workspace must be:

```
$ catkin_make -DPYTHON_EXECUTABLE=/usr/bin/python3
```

then,Sourcing setup.bash files will overlay this workspace on top of your environment.

```
source devel/setup.bash
```

check

```
$ echo $ROS_PACKAGE_PATH
/home/youruser/catkin_ws/src:/opt/ros/kinetic/share
```

3. Clone the myCobotROS package from github

```
$ cd ~/catkin_ws/src
$ git clone https://github.com/elephantrobotics/myCobotROS.git
$ cd ~/catkin_ws
$ catkin_make
```