插上can模块，打开终端，可用ifconfig -a命令查看所有端口，检查是否存在can0

根据需要设置can波特率

sudo ip link set can0 type can bitrate 500000

打开can口

sudo ip link set can0 up

终端需要先执行source，才能执行ros命令

source /home/mz/working/ROS/CANOpen/devel/setup.bash

连接can命令

rosrun socketcan\_bridge socketcan\_to\_topic\_node

接收命令

rosrun socketcan\_interface socketcan\_dump can0

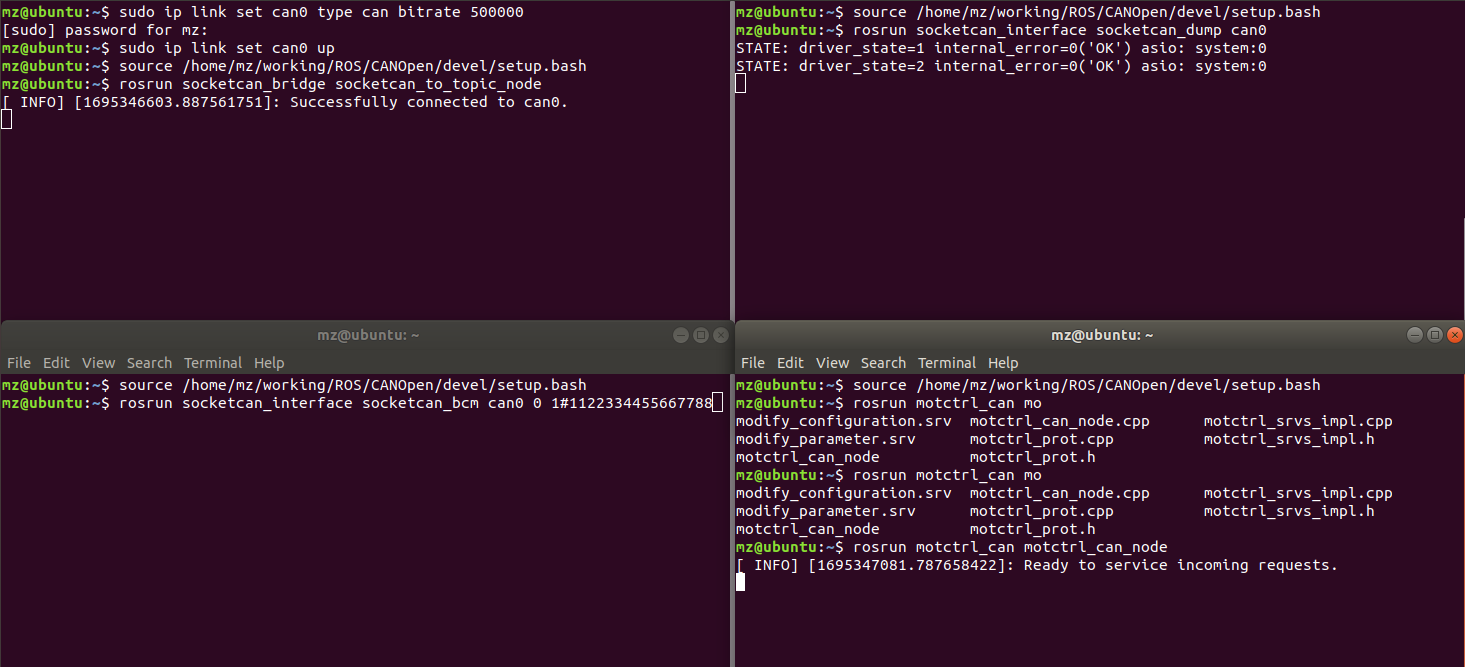
发送命令

rosrun socketcan\_interface socketcan\_bcm can0 0 1#1122334455667788

查看节点

rosrun motctrl\_can motctrl\_can\_node

终端界面演示



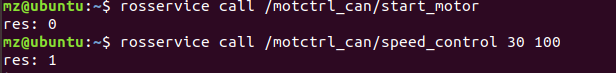
写入要发送端口和canid

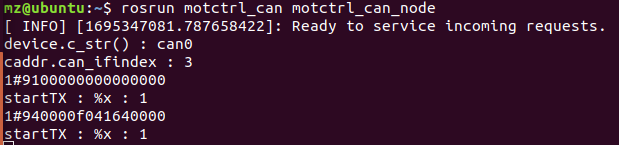


rosservice type /moctrl\_can/open\_can | rossrv show 查看服务参数信息

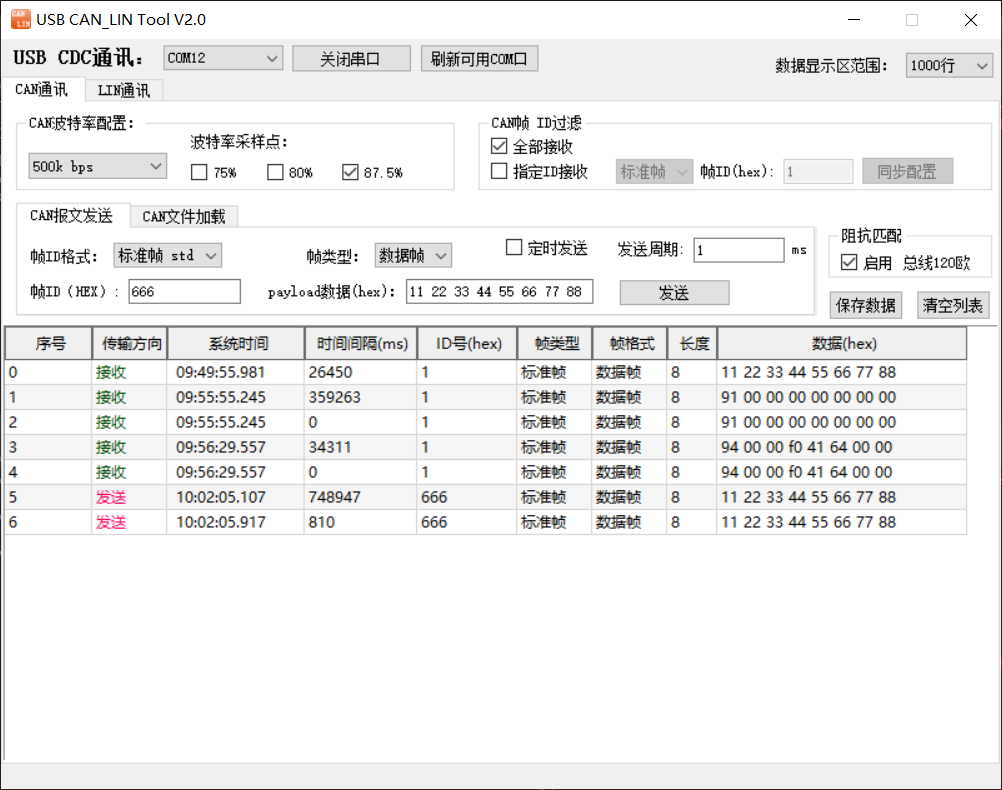
利用rosservice list命令查看可用服务

发送启动电机和速度控制30RPM





Windows下can通信助手信息展示



接收展示

