

Up--right--left--down keys values:

^[A ^[[C ^[[B ^[[D

Changes in code-

Line 96-99 initially

```
<script>
  <name>Gazebo/DarkGrey</name>
  <uri>file://media/materials/scripts/gazebo.material</uri>
</script>
```

Line 96-99 finally

```
<script>
  <uri>model://robo_car/materials/scripts</uri>
  <uri>model://robo_car/materials/logo</uri>
  <name>Logo/Robo</name>
</script>
```

Line 153-160 Left Wheel initially

```
<visual name="{ { model_name } }_front_left_wheel_collision_visual">
  <pose>0 0 0 0 1.57079632679 0</pose>
  <geometry>
    <cylinder>
      <radius>0.033</radius>
      <length>0.024</length>
    </cylinder>
  </geometry>
```

Line 155-160 Left Wheel finally

```
<visual name="{ { model_name } }_front_left_wheel_collision_visual">
  <pose>0 0 0 0 -0 3.141592653589793238</pose>
  <geometry>
    <mesh>
      <uri>model://robo_car/meshes/LeftWheel.stl</uri>
    </mesh>
  </geometry>
```

Line 230-237 Right Wheel initially

```
<visual name="{ { model_name } }_front_right_wheel_collision_visual">
  <pose>0 0 0 0 1.57079632679 0</pose>
  <geometry>
    <cylinder>
      <radius>0.033</radius>
      <length>0.024</length>
    </cylinder>
  </geometry>
```

Line 231-236 Right Wheel finally

```
<visual name="{ { model_name } }_front_right_wheel_collision_visual">
  <pose>0 0 0 0 3.141592653589793238 -3.141592653589793238</pose>
  <geometry>
    <mesh>
      <uri>model://robo_car/meshes/RightWheel.stl</uri>
    </mesh>
  </geometry>
```

Line 307-314 rear left wheel initially

```
<visual name="{ { model_name } }_rear_left_wheel_collision_visual">
  <pose>0 0 0 0 1.57079632679 0</pose>
  <geometry>
    <cylinder>
      <radius>0.033</radius>
      <length>0.024</length>
    </cylinder>
  </geometry>
```

Line 307-311 rear left wheel finally

```
<visual name="{ { model_name } }_rear_left_wheel_collision_visual">
  <pose>0 0 0 0 -0 3.141592653589793238</pose>
  <geometry>
    <mesh>
      <uri>model://robo_car/meshes/LeftWheel.stl</uri>
    </mesh>
  </geometry>
```

Line 383-390 rear right wheel initially

```
<visual name="{ { model_name } }_rear_right_wheel_collision_visual">
  <pose>0 0 0 0 1.57079632679 0</pose>
  <geometry>
    <cylinder>
      <radius>0.033</radius>
      <length>0.024</length>
    </cylinder>
  </geometry>
```

Line 382-387 rear right wheel finally

```
<visual name="{ { model_name } }_rear_right_wheel_collision_visual">
  <pose>0 0 0 0 3.141592653589793238 -3.141592653589793238</pose>
  <geometry>
    <mesh>
      <uri>model://robo_car/meshes/RightWheel.stl</uri>
    </mesh>
  </geometry>
```

After doing all this changes go in -

ros2ws -> robo_gazebo -> models -> robo_car -> materials -> logo and scripts

In the logo you can add the colour which you want to be on the car and first rename the old image from sample.jpg to name.jpg and add the image of the colour their and name it as sample.jpg

Further in scripts in logo.materials you can add the name(from logo folder) of the image.

For launching packages in SRC along with gazebo-

gen_params.json line 28-34. While installing the ros2ws package all files inside src were downloaded from the online repo with the site link where they are stored.

```
"ros2_repo_2":{
  "repo": "git@github.com:pr-db/track_follow.git",
  "version": "mini",
  "build_package": "track_follow",
  "build_prefix": "--packages-select",
  "build_postfix": "--symlink-install"
},
```

gen_params.json line 83-90 for launching a package along with the gazebo in the same terminal. Do changes as follows from track_follow(main folder name) and line_follower(name of folder in console scripts in setup.py of their respective folders).

```

"ros2_node_2":{
    "timing": "post-spawn",
    "package": "track_follow",
    "executable": "line_follower",
    "name": "line_follower_0",
    "output": "screen",
    "parameters": []
}

```

Error when we used the termios library from ros index1 teleop.

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[talker-7] Traceback (most recent call last):

[talker-7] File "/home/tirth/ros2ws/install/my_pubsub/lib/my_pubsub/talker", line 33, in
<module>

[talker-7] sys.exit(load_entry_point('my-pubsub', 'console_scripts', 'talker')())

[talker-7] File "/home/tirth/ros2ws/build/my_pubsub/my_pubsub/teleop_twist_keyboard.py", line
95, in main

[talker-7] settings = saveTerminalSettings()

[talker-7] File "/home/tirth/ros2ws/build/my_pubsub/my_pubsub/teleop_twist_keyboard.py", line
81, in saveTerminalSettings

[talker-7] return termios.tcgetattr(sys.stdin)

[talker-7] **termios.error: (25, 'Inappropriate ioctl for device')**

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<https://pypi.org/project/readchar/>