

Project cheat sheet

- Raspberry pi4
 - ✓ power the Rpi and connect it to the same network as the dev machine
 - ✓ open a terminal with 2 tabs, 3 windows each
 - ✓ in each window of the 3 of the First tab run “ ssh -o ServerAliveInterval=60 pi@192.168.84.12 “
make sure of the IP address
 - ✓ Enter Rpi password: **01145623392**

now that you have 3 opened windows connected to Rpi through SSH

“ **cd ros2_ws** “ in each window

- ✓ 1st window: **ros2 launch articubot_one launch_robot.launch.py**
- ✓ 2nd window : **ros2 launch articubot_one rplidar.launch.py** (or the run line of rplidar_composition from history)
- ✓ 3rd window : **ros2 run serial_motor number publisher**
Change between ACM0 and ACM1 in the node script if it gives an error

Note that you should run the above run lines on the Raspberry pi4

** Make sure Lidar and Arduino are connected to the Rpi

- Dev machine

** sudo apt update

sudo apt upgrade

** Make sure that you have the package downloaded in a workspace

Open the second tap (with 3 windows)

- ✓ Change directory to the workspace that contains package : **cd 'ur_ws'**
- ✓ 1st window : **rviz2**
- ✓ 2nd window: **ros2 launch slam_toolbox online_async_launch.py**
slam_params_file:=./src/articubot_one/config/mapper_params_online_async.yaml
use_sim_time:=false
- ✓ 3rd window: **ros2 run teleop_twist_keyboard teleop_twist_keyboard**

** Make sure you have all plugins and dependencies installed

- Twist mux
- Navigation and nav2_bringup
- Slam_toolbox
- Etc.