**Instructions for how to use the Repository.**

Before clone the repository, First need to install the ROS correctly. The instruction for installation has given in repository.

There are two packages: Line follower Boe-Bot and Maze follower Boe-Bot.

Clone the Packages inside the src folder of Catkin\_ws (catkin workspace)

## Catkin Workspace

[Catkin](http://wiki.ros.org/catkin) is a CMAKE-based build system used to build ROS packages.

## Catkin Setup

We will be setting up a Catkin Workspace on **the** Boe-Bot on following steps.

1. Open a new terminal and create your catkin workspace.
   1. Create a new directory in your home folder:
      * mkdir -p ~/catkin\_ws/src
   2. CD to that directory:
      * cd ~/catkin\_ws/src
   3. Initialize the workspace:
      * catkin\_init\_workspace
   4. Build the empty catkin workspace.
      * cd ~/catkin\_ws
      * catkin\_make
   5. Source the setup.sh file to load the environment setup.
      * source ~/catkin\_ws/devel/setup.sh
2. After making the workspace and cloning the repo to the src file. Compile the package by opening a terminal and put the command catkin\_make
   1. CD to your catkin\_ws src directory
      * catkin\_make

**About the scripts or python codes**

The codes are already in the scripts folder inside the boe-bot description folder. So, once you cloned the repository and compiled the codes in the script folder will also compiled with the package.

For launching the Line follower environment follow these steps:

* Open terminal
* Type roslaunch boe-bot\_description gazebo.launch

For launching the Maze follower environment follow these steps:

* Open terminal
* Type roslaunch boe-bot\_description Maze.launch
* Open another terminal and initialize the wall follower python code.
* roscore boe-bot\_description wall\_follower.py