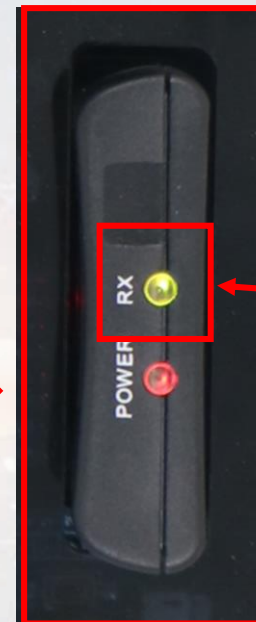
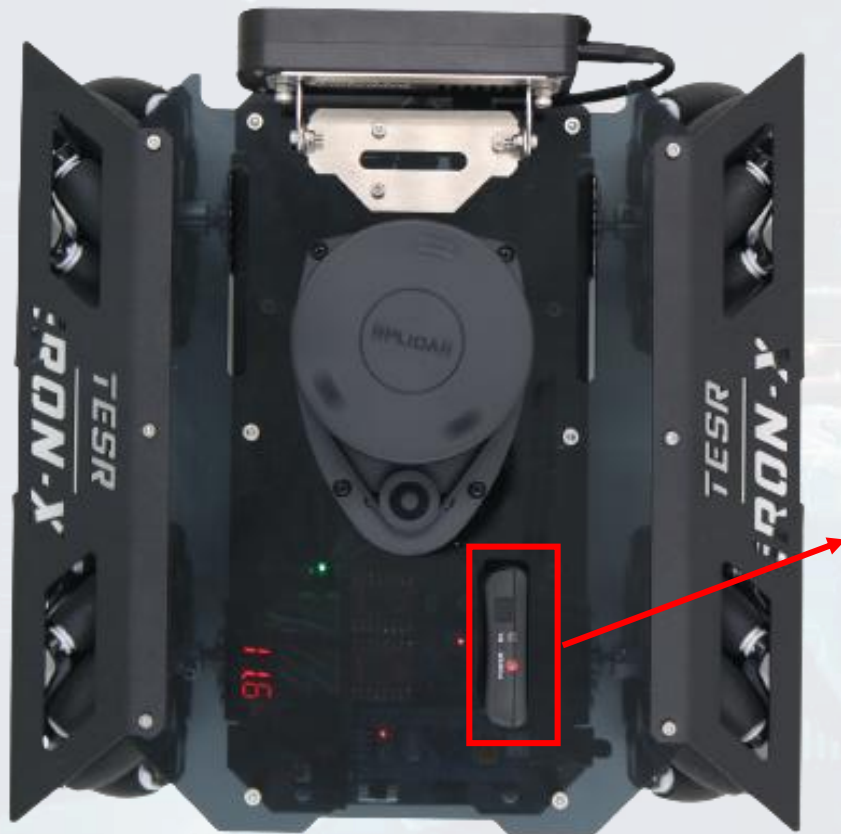




# iron-X with Keyboard & JoyStick By TESR

ROS2

# Control **iron-X** with JoyStick



Rx LED	Status
Blinking	Pairing
LED ON	Paired

# Control **iron-X** with JoyStick

Front-view



Back-view



Tx LED	Status
Blinking	Pairing
LED ON	Paired
LED OFF	Turn off or sleep

# Control **iron-X** with JoyStick



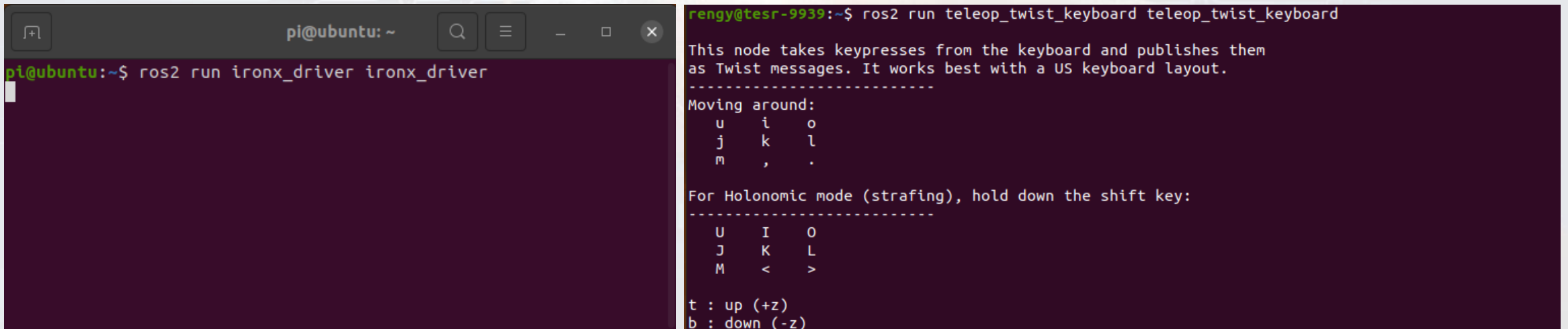
# iron-X with Keyboard control on ROS2

- You can activate keyboard to control iron-X using:
  - On first terminal, run ironx\_driver:

```
ros2 run ironx_bringup ironx_driver
```

- On second terminal, run teleop\_twist\_keyboard:

```
ros2 run teleop_twist_keyboard teleop_twist_keyboard
```



The image shows two terminal windows side-by-side. The left window is titled 'pi@ubuntu: ~' and shows the command 'ros2 run ironx\_driver ironx\_driver' being executed. The right window is titled 'rengy@tesr-9939:~\$' and shows the command 'ros2 run teleop\_twist\_keyboard teleop\_twist\_keyboard' being executed. Below the command, the terminal displays instructions for using the keyboard to control the robot, including a list of keys for moving around and a section for Holonomic mode (strafing) which requires holding down the shift key.

```
rengy@tesr-9939:~$ ros2 run teleop_twist_keyboard teleop_twist_keyboard
This node takes keypresses from the keyboard and publishes them
as Twist messages. It works best with a US keyboard layout.
-----
Moving around:
  u   i   o
  j   k   l
  m   ,   .

For Holonomic mode (strafing), hold down the shift key:
-----
  U   I   O
  J   K   L
  M   <   >

t : up (+z)
b : down (-z)
```



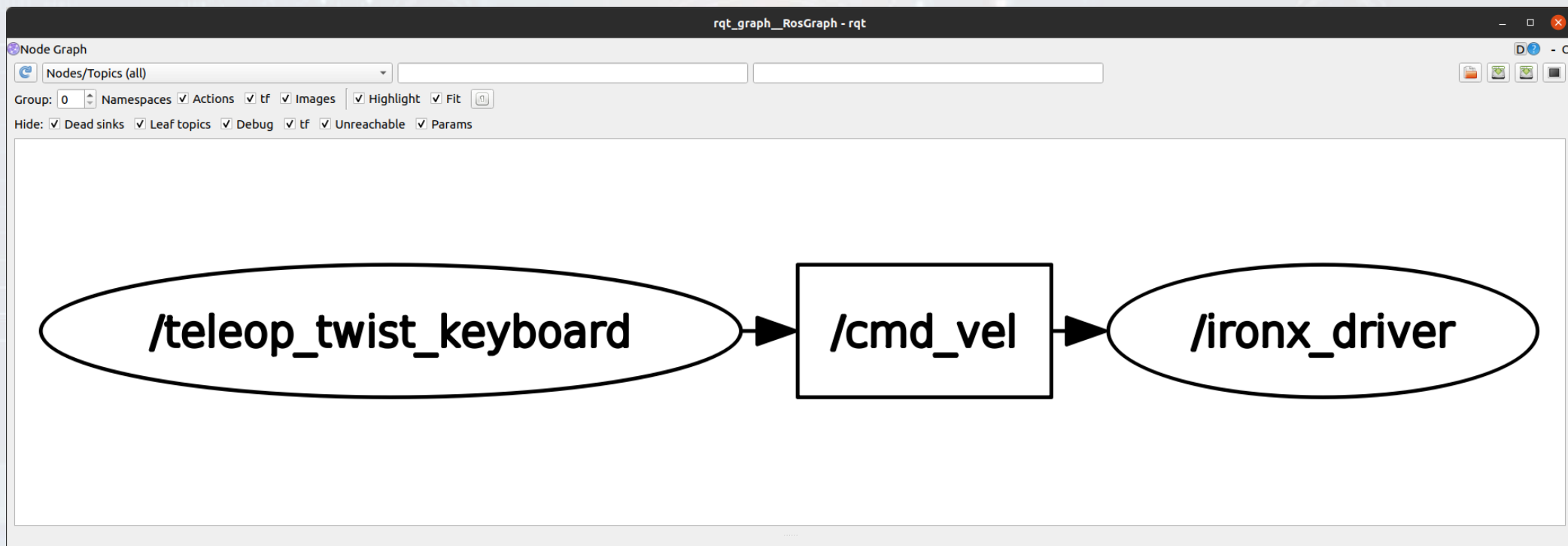
# iron-X with Keyboard control on ROS2



# RosGraph for **Keyboard** control on **ROS2**

- You can see the RosGraph by open new terminal and type:

```
rqt_graph
```



# Contact Us

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