1. roscore

2.启动新的终端就要

source ./devel/setup.zsh

3.启动can

sudo ip link set can0 up type can bitrate 250000

rosrun bike\_core can\_send\_receive\_node

1. 启动遥控器

给串口权限

sudo chmod 777 /dev/ttyUSB1

在文件中修改usb名保存

/home/hll/bike\_ws/src/bike-xuan/bike\_core/params/odrive\_motor\_config.yaml

rosrun bike\_core parser\_remote\_data\_node

查看遥控器话题

rostopic echo /parser\_remote\_data\_node/remote\_ctrl\_data

1. 启动舵机

给串口权限

sudo chmod 777 /dev/ttyUSB0

在文件中修改usb名保存

/home/hll/bike\_ws/src/bike-xuan/bike\_core/params/odrive\_motor\_config.yaml

rosrun bike\_core sbus\_simulate\_node

1. 启动IMU

给串口权限

sudo chmod 777 /dev/ttyUSB2

在文件中修改usb名要编译

/home/hll/bike\_ws/src/bike-xuan/imu\_ch100/serial\_imu/src/serial\_imu.cpp

roslaunch imu\_launch imu\_msg.launch

7.平衡

rosrun bike\_core bike\_xuan\_core\_control\_node

查看有几个串口

ls /dev/ttyUSB\*