Creating Launcher of URDF File for Workspace

urdf_tutorial is only used to test and debug the simulation but in order to use in our project, we need to integrate it in workspace. Follow these steps to make.

1. Create a folder named "*robotname_ws*" and navigate in it and make "*src*".
2. Colcon build it and *~/.bashrc* sourcing command.
3. Add a package *robotname_description* in *src* and remove include and *src* in it.
4. Create a new folder named urdf and add urdf file to it and also make *rviz_config* folder.
5. To create a launch file for urdf, ros2 has built-in nodes and topic that are used to handle it instead of creating new nodes. The nodes can be seen using *rqt_graph* when run with *urdf_tutorial*. See pic below

6. Copy and paste commands from cmakelist and xml.
7. Adjust according to your project.
8. Run it using *ros2 launch* command.