**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



1. Copy and paste commands from cmakelist and xml.
2. Adjust according to your project.
3. Run it using ***ros2 launch*** command.