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ENPM662 – Fall 2022

Project 0

Project 0: Install and Set up Ros Environment

Currently working on machine that is preinstalled with Ubuntu 18.04 Lts, and ROS Melodic.
Hence, no Ubuntu installation required.

lsb_release -a

```
jossi@jossi-HP-350-G1:~$ lsb_release -a
No LSB modules are available.
Distributor ID: Ubuntu
Description:    Ubuntu 18.04.6 LTS
Release:        18.04
Codename:       bionic
jossi@jossi-HP-350-G1:~$
```

Checking git version installed on machine

git --version

```
jossi@jossi-HP-350-G1:~$ git --version
git version 2.17.1
jossi@jossi-HP-350-G1:~$
```

Checking proper installation of ROS on system

roscore

```
jossi@jossi-HP-350-G1:~$ roscore
... logging to /home/jossi/.ros/log/b6cbd8ec-2f08-11ed-883f-1008b146bbaf/roslaun
ch-jossi-HP-350-G1-10934.log
Checking log directory for disk usage. This may take a while.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://jossi-HP-350-G1:40023/
ros_comm version 1.14.13

SUMMARY
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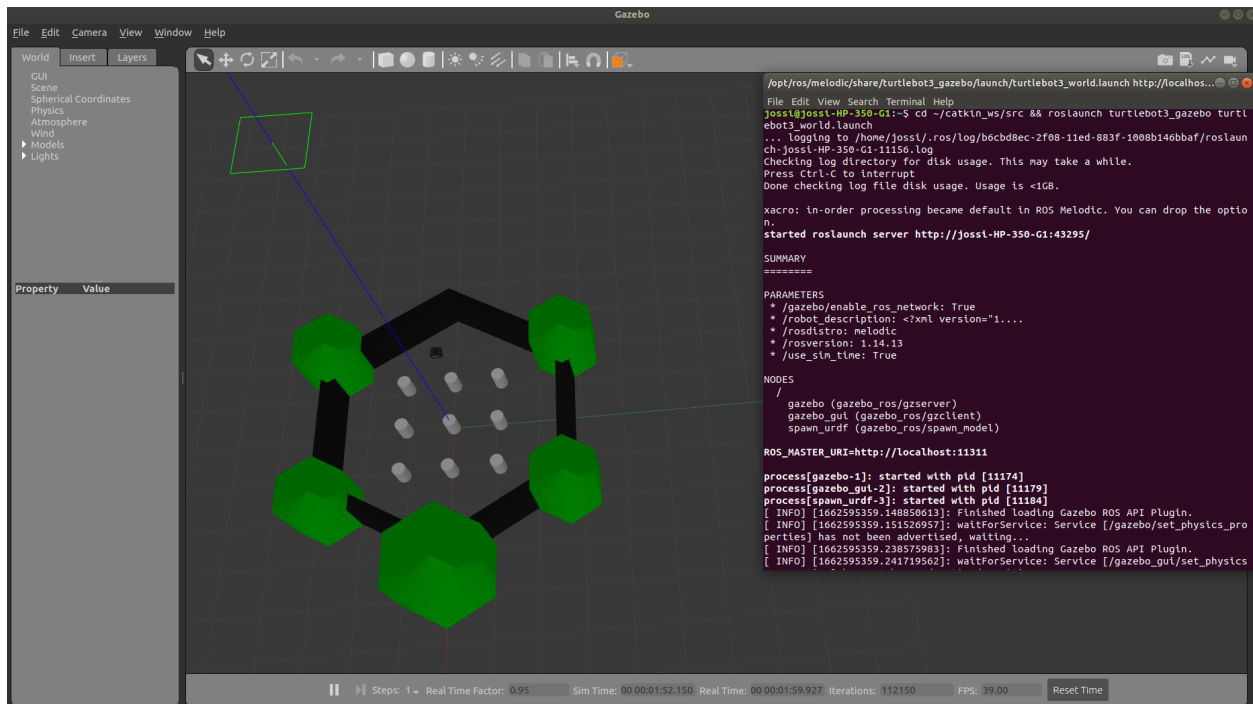
PARAMETERS
* /rostdistro: melodic
* /rosversion: 1.14.13

NODES
auto-starting new master
process[master]: started with pid [10945]
ROS_MASTER_URI=http://jossi-HP-350-G1:11311/

setting /run_id to b6cbd8ec-2f08-11ed-883f-1008b146bbaf
process[rosout-1]: started with pid [10956]
started core service [/rosout]
```

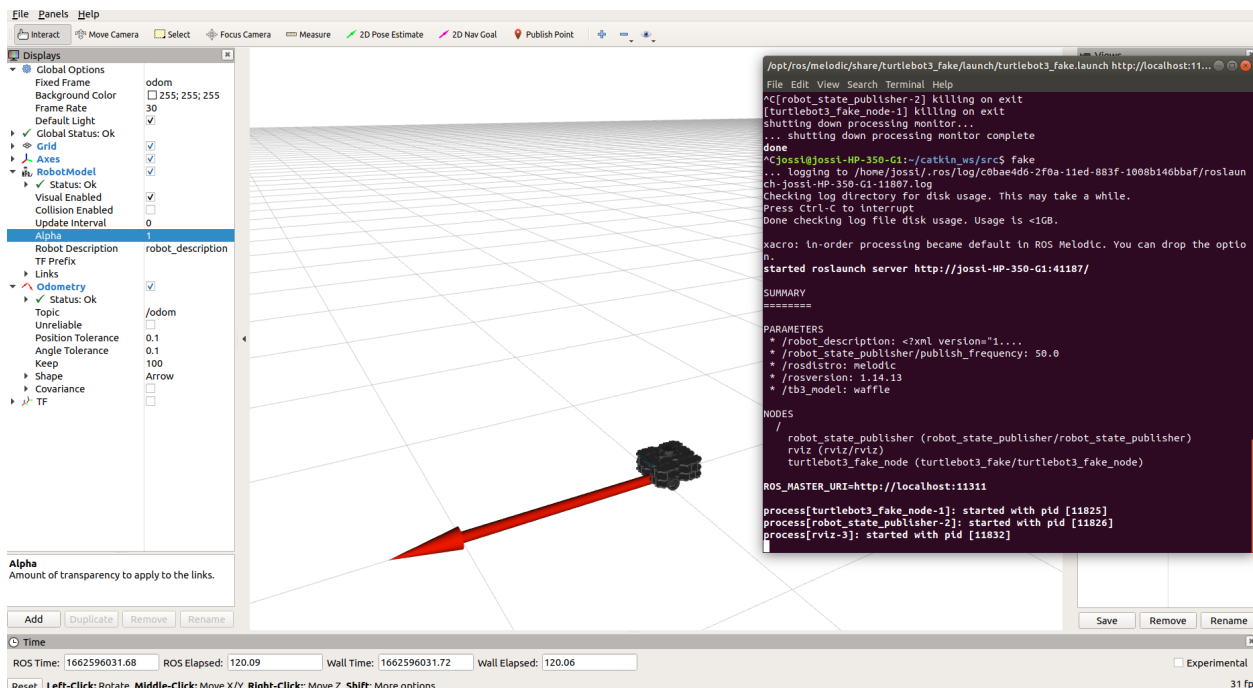
Checking gazebo installation

cd ~/catkin_ws/src && roslaunch turtlebot3_gazebo turtlebot3_world.launch



Checking gazebo installation

cd ~/catkin_ws/src && roslaunch turtlebot3_fake turtlebot3_fake.launch



Checking teleop robot control

roslaunch turtlebot3_teleop turtlebot3_teleop_key.launch

https://youtu.be/_ubn6lqdAzA