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☰ README.md

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# KUBOT ROS1 WORKSPACE V2.2



KUBOT ROS package is developed by Taiwan ShaYangYe Co.Ltd RD400. Thanks to ROS wiki, Turtlebot, Pibot, Neuronbot and a large number of ROS users. This package includes the functions to bring up the kubot robot, to make it SLAM, to Navigation, and to simulate it with your own computer.

## Install KUBOT ROS

Currently supports Kinetic and Melodic ROS versions

1. [Install ROS](#)
2. Download KUBOT package

```
git clone https://github.com/kubot080301/kubot2_ros.git
```

3. Install KUBOT ROS dependency package

```
./kubot2_ros/tools/kubot_install_ros.sh
```

4. Initialization environment

```
./kubot2_ros/kubot_init_env.sh
```

After starting the script, you will encounter several options:

- please specify kubot model
- please specify kubot driver board type

- please specify your kubot lidar
- please specify the current machine
  - Enter 0 for ROS master, Enter 1 and keyin ip for ROS slave

```
source ~/.bashrc
```

This script uses bash shell by default. If you use other shells, please modify all `bashrc` and `bash` words in the script.

#### 5. Create ROS workspace

```
cd ~/kubot2_ros/ros_ws  
catkin_make  
source ~/.bashrc
```

Then you can enjoy KUBOT ROS !!

try `roslaunch` or `keyin kubot_ TAB TAB`, You can see many of the features command

```
roslaunch kubot_bringup bringup.launch  
roslaunch kubot_navigation gmapping.launch
```

## KUBOT2\_ROS





## Releases

No releases published  
[Create a new release](#)

## Packages

No packages published  
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## Contributors 2

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## Languages

