cmake\_minimum\_required(VERSION 2.8.3)

project(irobot\_prj)

## Find catkin macros and libraries

## if COMPONENTS list like find\_package(catkin REQUIRED COMPONENTS xyz)

## is used, also find other catkin packages

find\_package(catkin REQUIRED COMPONENTS

roscpp

rospy

std\_msgs

)

## System dependencies are found with CMake's conventions

# find\_package(Boost REQUIRED COMPONENTS system)

## Uncomment this if the package has a setup.py. This macro ensures

## modules and global scripts declared therein get installed

## See http://ros.org/doc/api/catkin/html/user\_guide/setup\_dot\_py.html

# catkin\_python\_setup()

################################################

## Declare ROS messages, services and actions ##

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## To declare and build messages, services or actions from within this

## package, follow these steps:

## \* Let MSG\_DEP\_SET be the set of packages whose message types you use in

## your messages/services/actions (e.g. std\_msgs, actionlib\_msgs, ...).

## \* In the file package.xml:

## \* add a build\_depend and a run\_depend tag for each package in MSG\_DEP\_SET

## \* If MSG\_DEP\_SET isn't empty the following dependencies might have been

## pulled in transitively but can be declared for certainty nonetheless:

## \* add a build\_depend tag for "message\_generation"

## \* add a run\_depend tag for "message\_runtime"

## \* In this file (CMakeLists.txt):

## \* add "message\_generation" and every package in MSG\_DEP\_SET to

## find\_package(catkin REQUIRED COMPONENTS ...)

## \* add "message\_runtime" and every package in MSG\_DEP\_SET to

## catkin\_package(CATKIN\_DEPENDS ...)

## \* uncomment the add\_\*\_files sections below as needed

## and list every .msg/.srv/.action file to be processed

## \* uncomment the generate\_messages entry below

## \* add every package in MSG\_DEP\_SET to generate\_messages(DEPENDENCIES ...)

## Generate messages in the 'msg' folder

# add\_message\_files(

# FILES

# Message1.msg

# Message2.msg

# )

## Generate services in the 'srv' folder

# add\_service\_files(

# FILES

# Service1.srv

# Service2.srv

# )

## Generate actions in the 'action' folder

# add\_action\_files(

# FILES

# Action1.action

# Action2.action

# )

## Generate added messages and services with any dependencies listed here

# generate\_messages(

# DEPENDENCIES

# std\_msgs

# )

###################################

## catkin specific configuration ##

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## The catkin\_package macro generates cmake config files for your package

## Declare things to be passed to dependent projects

## INCLUDE\_DIRS: uncomment this if you package contains header files

## LIBRARIES: libraries you create in this project that dependent projects also need

## CATKIN\_DEPENDS: catkin\_packages dependent projects also need

## DEPENDS: system dependencies of this project that dependent projects also need

catkin\_package(

# INCLUDE\_DIRS include

# LIBRARIES irobot\_prj

# CATKIN\_DEPENDS roscpp rospy std\_msgs

# DEPENDS system\_lib

)

###########

## Build ##

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## Specify additional locations of header files

## Your package locations should be listed before other locations

# include\_directories(include)

include\_directories(

${catkin\_INCLUDE\_DIRS}

)

## Declare a cpp library

# add\_library(irobot\_prj

# src/${PROJECT\_NAME}/irobot\_prj.cpp

# )

## Declare a cpp executable

# add\_executable(irobot\_prj\_node src/irobot\_prj\_node.cpp)

## Add cmake target dependencies of the executable/library

## as an example, message headers may need to be generated before nodes

# add\_dependencies(irobot\_prj\_node irobot\_prj\_generate\_messages\_cpp)

## Specify libraries to link a library or executable target against

# target\_link\_libraries(irobot\_prj\_node

# ${catkin\_LIBRARIES}

# )

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## Install ##

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# all install targets should use catkin DESTINATION variables

# See http://ros.org/doc/api/catkin/html/adv\_user\_guide/variables.html

## Mark executable scripts (Python etc.) for installation

## in contrast to setup.py, you can choose the destination

# install(PROGRAMS

# scripts/my\_python\_script

# DESTINATION ${CATKIN\_PACKAGE\_BIN\_DESTINATION}

# )

## Mark executables and/or libraries for installation

# install(TARGETS irobot\_prj irobot\_prj\_node

# ARCHIVE DESTINATION ${CATKIN\_PACKAGE\_LIB\_DESTINATION}

# LIBRARY DESTINATION ${CATKIN\_PACKAGE\_LIB\_DESTINATION}

# RUNTIME DESTINATION ${CATKIN\_PACKAGE\_BIN\_DESTINATION}

# )

## Mark cpp header files for installation

# install(DIRECTORY include/${PROJECT\_NAME}/

# DESTINATION ${CATKIN\_PACKAGE\_INCLUDE\_DESTINATION}

# FILES\_MATCHING PATTERN "\*.h"

# PATTERN ".svn" EXCLUDE

# )

## Mark other files for installation (e.g. launch and bag files, etc.)

# install(FILES

# # myfile1

# # myfile2

# DESTINATION ${CATKIN\_PACKAGE\_SHARE\_DESTINATION}

# )

#############

## Testing ##

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## Add gtest based cpp test target and link libraries

# catkin\_add\_gtest(${PROJECT\_NAME}-test test/test\_irobot\_prj.cpp)

# if(TARGET ${PROJECT\_NAME}-test)

# target\_link\_libraries(${PROJECT\_NAME}-test ${PROJECT\_NAME})

# endif()

## Add folders to be run by python nosetests

# catkin\_add\_nosetests(test)