**How to turn on and off**

Passwords are: locobot

Power on

Battery: one time click  
Locobot’s Computer; one time click.

Mobile base (create 3): inserting the dock

Power off

Battery: hold the bottom for 3 sec.  
Locobot’s Computer; sudo poweroff.

Mobile base (create 3): hold its bigger bottom for 10 sec

**For Setup Locobot from scratch**

How to run the Locobot if It is crashed? (If not, do not use this tutorial)  
  
You need a remote computer to send the commands and receive data from the Locobot’s computer.  
After connecting a monitor, mouse and keyboard to the locobot you need to install different packages on both locobot and remote computer.

**For remote Computer:**

1- Intstalling Uunutu 20.04 from

wsl --install -d Ubuntu-20.04

2- install ROS rvis and rosdep

2- Edit the file of bashrc with this command: (gedit ~/.bashrc) and check if these part are added or add this parts:

source /opt/ros/noetic/setup.bash

# Interbotix Configurations

source /home/mhsnar/interbotix\_ws/devel/setup.bash

export RMW\_IMPLEMENTATION=rmw\_fastrtps\_cpp

export INTERBOTIX\_XSLOCOBOT\_BASE\_TYPE=create3

export ROS\_MASTER\_URI=http://192.168.1.4:11311

export ROS\_IP=$(echo `hostname -I | cut -d" " -f1`)

if [ -z "$ROS\_IP" ]; then

export ROS\_IP=127.0.0.1

fi

**For Robot’s Computer**

1- Intstalling Uunutu 20.04 from booted flash.

2- update and upgrde apt

3- reboot

4- Install interbotix pakage (Do not instsall ROS seperately)

5- Base Connection check (Installation step for base in troubleshooting part of the cite)

6- Run the code

Note: If remote control did not work go to chenge bash rc to edit like this:

#export ROS\_IP=$(echo `hostname -I | cut -d" " -f1`)

#if [ -z "$ROS\_IP" ]; then

# export ROS\_IP=127.0.0.1

#fi

export ROS\_ID=192.168.1.4

**For Doing SLAM via joystick movement**

ROBOT:

roslaunch interbotix\_xslocobot\_nav xslocobot\_nav.launch robot\_model:=locobot\_wx250s use\_lidar:=true rtabmap\_args:=-d

ROBOT:

roslaunch interbotix\_xslocobot\_joy xslocobot\_joy.launch robot\_model:=locobot\_wx250s launch\_driver:=false

Remote:

roslaunch interbotix\_xslocobot\_descriptions remote\_view.launch rviz\_frame:=map

**Some hints**

ros2 topic list

ros2 topic inof /(topic name)

ros2 interface show (massage)

rosmsg show

ros2 topic echo /(topic name)