ROS – Sensore forza (Comau) + Sensori tattili

Terminale 1 – CORE
roscore

Terminale 2 – PLOTJUGGLER
plotjuggler-ros

Terminale 3 – SENSORE DI FORZA (COMAU)
cd ros
cd atift_ws/
source devel/setup.bash *(oppure* so*)*
roslaunch atift_sensor atift.launch

Terminale 4 – PUBLISHER
cd /dev
sudo chmod 666 ttyUSB0
Inserisci password: sotomayor
cd
cd ros
cd sensor_ws
source devel/setup.bash *(oppure* so*)*
rosrun sensor_controller SimpleRead.py

Terminale 5 – SUBSCRIBER
cd ros
cd sensor_ws
source devel/setup.bash *(oppure* so*)*
rosrun sensor_controller SimpleRecorder.py

Terminale 6 – STREAM
cd ros
cd sensor_ws
source devel/setup.bash *(oppure* so*)*
rosrun sensor_controller plot_signals.py
Enter per avviare stream

Terminale 7 – SERVICE
cd ros
cd sensor_ws
source devel/setup.bash *(oppure* so*)*
rosservice call /atift_sensor /reset_bias "{}"
rosservice call /record "start: true"
rosservice call /record "start: false"

Altri comandi
ll / ls
cd
rostopic list
rosservice list
rosnode list
rostopic echo /atift_sensor /data

<table>
<tr><td>service</td><td>recorder</td><td>stream</td></tr>
<tr><td rowspan="2">read</td><td rowspan="2">atift</td><td>roscore</td></tr>
<tr><td>plotjuggler</td></tr>
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