**ROS – Sensore forza (Comau) + Sensori tattili**

|  |  |  |
| --- | --- | --- |
| service | recorder | stream |
| read | atift | roscore |
| plotjuggler |

**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