(Forked from <https://github.com/Factor-Robotics/odrive_ros2_control>)

# odrive\_ros2\_control

ENGLISH / [中文](https://bitbucket.org/mechatronica/odrive_ros2_control/src/455bab53f3352fa4845170cbda527c069d7a6259/README_CN.md)

## Introduction

ODrive driver for ros2\_control

!Driver adapted for the T-bot mechanism (combined motion) and for the motion compensation algorithm.

## Prerequisites

* ROS Foxy
* ODrive Firmware v0.5.3

## Documentation

* [Wiki](https://github.com/Factor-Robotics/odrive_ros2_control/wiki/Documentation)

## Done

* [x] Support native protocol on USB
* [x] Support position, speed, torque commands
* [x] Support position, speed, torque feedbacks
* [x] Support using multiple ODrives
* [x] Support smooth switching of control modes
* [x] Unit conversion adheres to [REP-103](https://www.ros.org/reps/rep-0103.html)
* [x] Support using any or both of axes on each ODrive
* [x] Allow multiple axes running in different control modes
* [x] Provide sensor data (error, voltage, temperature)
* [x] Auto watchdog feeding

## Todo

* [ ] Support serial port and CAN
* [ ] Support feedforward control inputs
* [ ] Automatic configuration of ODrives based on URDF and YAML files