**一. ROS\_Melodic安装——ubuntu18.04**

1.ubuntu16.04与ros\_kinetic匹配， ubuntu18.04与 ros\_melodic匹配

2.按照官网链接安装melodic：<http://wiki.ros.org/melodic/Installation/Ubuntu>

3.sudo rosdep init 报错解决：

<https://blog.csdn.net/wjjwangde/article/details/109808371>

4.

**二.Azure Kinect SDK 安装 支持的操作系统为Ubuntu18.04**

1.使用apt方式安装 （看到有的博客是用源码编译的方式进行安装的）

1.1 先配置Microsoft的包存储库

curl -sSL https://packages.microsoft.com/keys/microsoft.asc | sudo apt-key add -

sudo apt-add-repository <https://packages.microsoft.com/ubuntu/18.04/prod>

sudo apt-get update

官网链接：<https://docs.microsoft.com/zh-cn/windows-server/administration/linux-package-repository-for-microsoft-software>

1.2 安装SDK

sudo apt install k4a-tools

sudo apt install libk4a1.1-dev

官网链接：<https://docs.microsoft.com/zh-cn/azure/Kinect-dk/sensor-sdk-download>

sudo apt install libk4a1.4-dev

home目录

git clone -b v1.4.0 <https://github.com/microsoft/Azure-Kinect-Sensor-SDK.git>

下载依赖项：在~/Azure-Kinect-Sensor-SDK/scripts/docker 路径下找到setup-ubuntu.sh文件，右击->属性->权限->  
勾选允许作为程序执行文件

cd /Azure-Kinect-Sensor-SDK/scripts/docker

sudo chmod 777 setup-ubuntu.sh

sudo sh setup-ubuntu.sh

出现了一个Syntax error: “(” unexpected 的报错，通过以下命令解决

sudo dpkg-reconfigure dash 选择NO就行

1.3 运行k4aiewer进行安装测试

sudo k4aviewer

1.4 取消root权限启动

下载99-k4a.rules文件，并将其复制到/etc/udev/rules.d/ 目录中

sudo cp scripts/99-k4a.rules /etc/udev/rules.d/.

99-k4a.rules链接 <https://github.com/microsoft/Azure-Kinect-Sensor-SDK/blob/develop/scripts/99-k4a.rules>

**三. ROS packet安装使用**

1. 下载 package

cd catkin\_ws/src

git clone https://github.com/microsoft/Azure\_Kinect\_ROS\_Driver.git

**2.修改 k4a\_ros\_device.h**

路径：Azure\_Kinect\_ROS\_Driver/include/azure\_kinect\_ros\_driver/k4a\_ros\_device.h

*// Last capture timestamp for synchronizing playback capture and imu thread*

**-** std**::**atomic\_int64\_t last\_capture\_time\_usec\_;

**+** std**::**atomic**<int64\_t>** last\_capture\_time\_usec\_;

*// Last imu timestamp for synchronizing playback capture and imu thread*

**-** std**::**atomic\_uint64\_t last\_imu\_time\_usec\_;

**-** std**::**atomic\_bool imu\_stream\_end\_of\_file\_;

**+** std**::**atomic**<uint64\_t>** last\_imu\_time\_usec\_;

**+** std**::**atomic**<bool>** imu\_stream\_end\_of\_file\_;

**3.编译**

cd catkin\_ws

catkin\_make

**4.测试**

roslaunch azure\_kinect\_ros\_driver driver.launch

*# Global Fixed Frame: rgb\_camera\_link*

rostopic list