

مهمة تثبيت ROS



config.rviz - RViz

Interact Move Camera Select Focus Camera Measure 2D Pose Estimate 2D Nav Goal Publish Point

Displays

- Global Options
 - Fixed Frame: base
 - Background Color: 48; 48; 48
 - Frame Rate: 30
 - Default Light: ☒
 - Global Status: Ok
 - Fixed Frame: OK
 - Grid: ☒
 - Axes: ☒
 - Status: Ok
 - Reference Frame: <Fixed Frame>
 - Length: 1
 - Radius: 0.0
 - RobotModel: ☒
 - Status: Ok
 - Visual Enabled: ☒
 - Collision Enabled: ☐

Add Duplicate Remove Rename

Views

Type: Orbit (rviz) Zero

Current View: Orbit (rviz)

Near Clip ...	0.1
Invert Z Axis	<input type="checkbox"/>
Target Fra...	<Fixed Frame>
Distance	6.18737
Focal Shap...	0.0
Focal Shap...	<input checked="" type="checkbox"/>
Yaw	1.1208
Pitch	-0.00391
Focal Point	-1.2241; -2.4556; ...

Save Remove Rename

Time

ROS Time: 189520532.28 ROS Elapsed: 361.04 Wall Time: 1689520532.30 Wall Elapsed: 361.00 ☐ Experimental

Reset RViz is ready. 22 fps

```
ws/src/arduino_robot_arm/robot_arm_pkg/launch/check_motors.launch
version="1....
```

```
(joint_state_publisher_gui/joint_state_publisher_gui)
robot_state_publisher/robot_state_publisher)
```

```
h pid [7126]
ost:11311
23ea-11ee-82eb-080027da8cd3
th pid [7139]
t]
r-2]: started with pid [7142]
h pid [7143]
_gul-4]: started with pid [7144]
centering
```

joint_state_publisher

base_joint 0.15

shoulder 0.00

elbow 0.00

wrist 0.00

Randomize

Center

0

```
at the end of the (bashrc) file add the following line
(source /home/wesam/catkin_ws/devel/setup.bash)
then
ctrl + o
source ~/.bashrc
roslaunch robot_arm_pkg check_motors.launch
```