Task Tow:

1- Create ros1_bridge workspace and clone the package

```
mkdir -p ~/ros1_bridge_ws/src
```

```
fantidEadiNassei:~$ mkdir -p ~/ros1_bridge_ws/src
fadi@adiNassei:~$ cd cd ~/ros1_bridge_ws/src
-bash: cd: too many arguments
fadi@adiNassei:~$ cd ~/ros1_bridge_ws/src
fantideadiNassei:~/ros1_bridge_ws/src$
```

```
fadi@adiNassei:~/ros1_bridge_ws/src$ git clone -b foxy https://github.com/ros2/ros1_bridge.git
Cloning into 'ros1_bridge'...
remote: Enumerating objects: 1556, done.
remote: Counting objects: 100% (600/600), done.
remote: Compressing objects: 100% (59/59), done.
remote: Total 1556 (delta 568), reused 541 (delta 541), pack-reused 956
Receiving objects: 100% (1556/1556), 1.56 MiB | 799.00 KiB/s, done.
Resolving deltas: 100% (968/968), done.
fadi@adiNassei:~/ros1_bridge_ws/src$
```

```
~/ros1_bridge_ws/src$ Source ROS1 and ROS2 setup bash files
```

```
~/ros1_bridge_ws/src$ source ~/ros2_ws/install/setup.bash
```

```
:~/ros1_bridge_ws/src$ colcon build --packages-select ros1_bridge --cmake-force-configure --cmake-args -DBUILD_TESTING=FALSE
```

```
/ros1_bridge_ws/src$ source install/local_setup.bash
```

```
/ros1_bridge_ws/src$ ros2 run ros1_bridge dynamic_bridge --print-pairs
```

```
~/ros1_bridge_ws/src$ source /opt/ros/noetic/setup.bash
```

```
~/ros1_bridge_ws/src$ source ~/catkin_ws/devel/setup.bash
```

```
~/ros1_bridge_ws/src$ roslaunch robot_arm_pkg check_motors.launch
```

```
~/ros1_bridge_ws/src$ rostopic list
```

```
~/ros1_bridge_ws/src$ source install/setup.bash
```

```
:~/ros1_bridge_ws/src$ ros2 run ros1_bridge dynamic_bridge
```

```
~/ros1_bridge_ws/src$ source /opt/ros/foxy/setup.bash
```

```
~/ros1_bridge_ws/src$ ros2 topic echo /joint_states sensor_msgs/msg/JointState
```