# Steps of downloaded and starting the arm package

1-first open the terminal:

2-downloade the package arm by using code and that is up your computer,
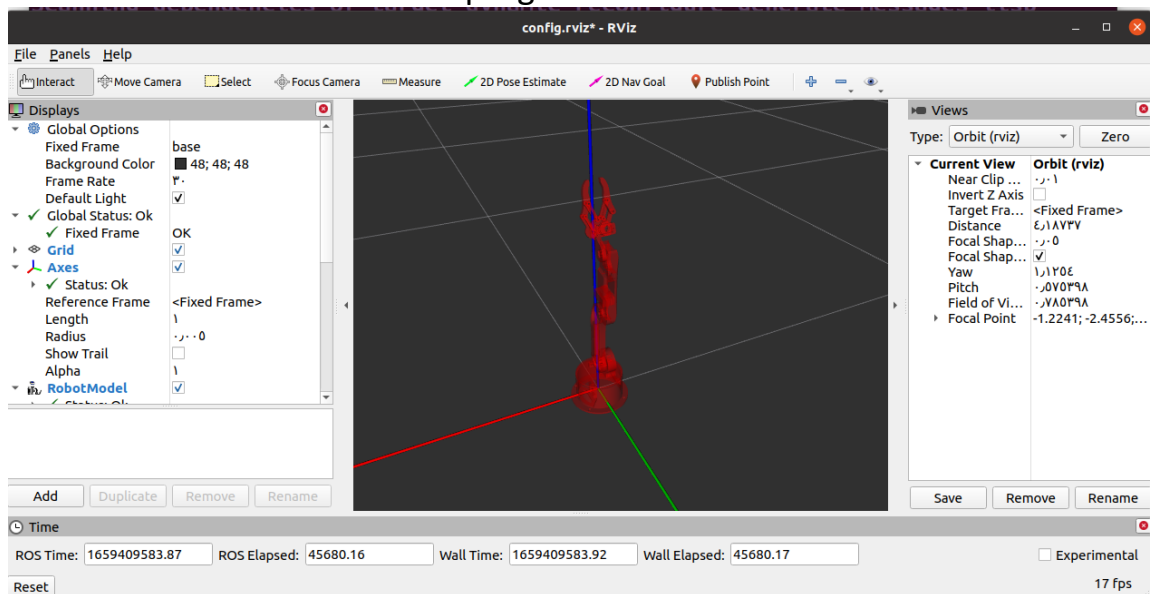
Some computer is using notice code and the another is using kinetic.

3-for the notice you will be using this code https://s-m.com.sa/ros/ros.txt

, and if your computer using kinetic you will be using this code  https://s-m.com.sa/ros.txt

4-you will be finish !! greet jop  :

This is the final work !! the program for Rvis is download and this arms.



When I work, I was finding some problems?

1

```
CMake Error at /opt/ros/noetic/share/catkin/cmake/catkinConfig.cmake:83 (find_p
ackage):
  Could not find a package configuration file provided by
  "moveit_ros_planning" with any of the following names:

    moveit_ros_planningConfig.cmake
    moveit_ros_planning-config.cmake

  Add the installation prefix of "moveit_ros_planning" to CMAKE_PREFIX_PATH
  or set "moveit_ros_planning_DIR" to a directory containing one of the above
  files.  If "moveit_ros_planning" provides a separate development package or
  SDK, be sure it has been installed.
Call Stack (most recent call first):
  arduino_robot_arm/moveit_pkg/CMakeLists.txt:6 (find_package)


-- Configuring incomplete, errors occurred!
See also "/home/yaser/catkin_ws/build/CMakeFiles/CMakeOutput.log".
See also "/home/yaser/catkin_ws/build/CMakeFiles/CMakeError.log".
Invoking "cmake" failed
```
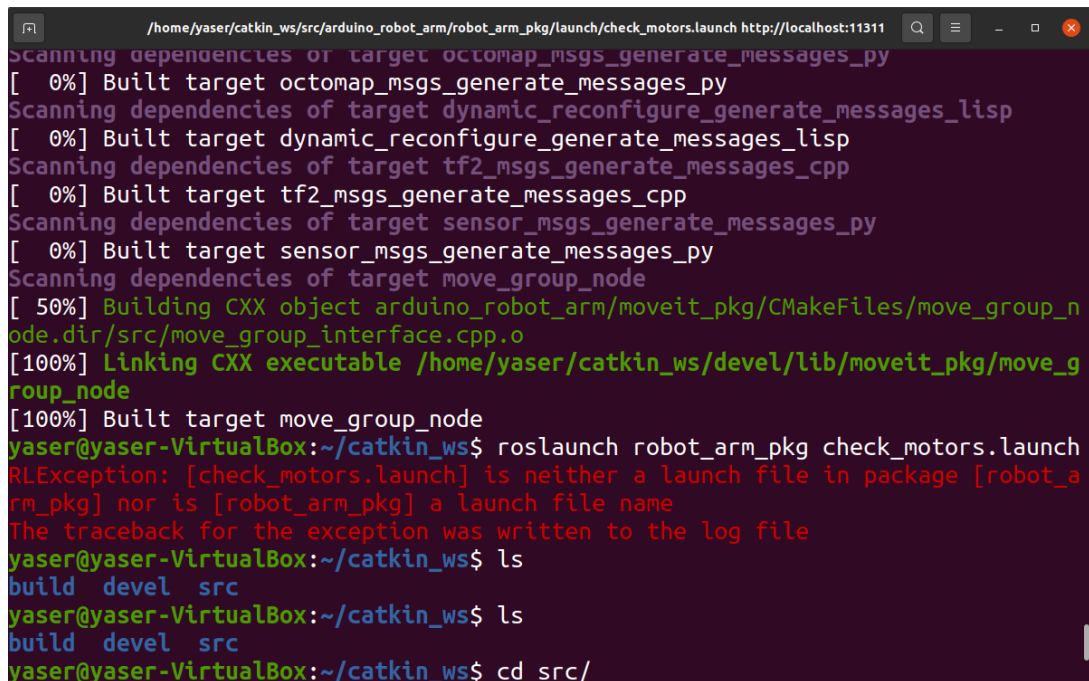
2-

```
/home/yaser/catkin_ws/src/arduino_robot_arm/robot_arm_pkg/launch/check_motors.launch http://localhost:11311
Scanning dependencies of target octomap_msgs_generate_messages_py
[  0%] Built target octomap_msgs_generate_messages_py
Scanning dependencies of target dynamic_reconfigure_generate_messages_lisp
[  0%] Built target dynamic_reconfigure_generate_messages_lisp
Scanning dependencies of target tf2_msgs_generate_messages_cpp
[  0%] Built target tf2_msgs_generate_messages_cpp
Scanning dependencies of target sensor_msgs_generate_messages_py
[  0%] Built target sensor_msgs_generate_messages_py
Scanning dependencies of target move_group_node
[ 50%] Building CXX object arduino_robot_arm/moveit_pkg/CMakeFiles/move_group_n
ode.dir/src/move_group_interface.cpp.o
[100%] Linking CXX executable /home/yaser/catkin_ws/devel/lib/moveit_pkg/move_g
roup_node
[100%] Built target move_group_node
yaser@yaser-VirtualBox:~/catkin_ws$ roslaunch robot_arm_pkg check_motors.launch
RLException: [check_motors.launch] is neither a launch file in package [robot_a
rm_pkg] nor is [robot_arm_pkg] a launch file name
The traceback for the exception was written to the log file
yaser@yaser-VirtualBox:~/catkin_ws$ ls
build  devel  src
yaser@yaser-VirtualBox:~/catkin_ws$ ls
build  devel  src
yaser@yaser-VirtualBox:~/catkin_ws$ cd src/
```

And I was take more time to solve it …


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THINK YOU