Command ROS

Berikut adalah semua command ROS yang digunakan untuk menjalankan simulasi.

Chapter 2. Getting Started with ROS Programming

- roscore
- rosrun mastering_ros_demo_pkg demo_to_pic_publisher
- rosrun mastering_ros_demo_pkg demo_to_pic_subscriber
- rosrun mastering_ros_demo_pkg demo_msg_publisher
- rosrun mastering_ros_demo_pkg demo_msg_subscriber
- rosrun mastering_ros_demo_pkg demo_service_server
- rosrun mastering_ros_demo_pkg demo_service_client
- rosrun mastering_ros_demo_pkg demo_action_server
- rosrun mastering_ros_demo_pkg demo_action_client 10 1

Chapter 3. Working with ROS for 3D Modeling

- roslaunch mastering_ros_robot_description_pkg view_demo.launch
- roslaunch mastering_ros_robot_description_pkg view_arm.launch
- roslaunch mastering_ros_robot_description_pkg view_mobile_robot.launch

Chapter 4. Simulating Robots Using ROS and Gazebo

- roslaunch seven_dof_arm_gazebo seven_dof_arm_gazebo_control.launch
- rostopic pub /seven_dof_arm/joint4_position_controller/command std_msgs/Float64 "data: 1.0"
- roslaunch diff_wheeled_robot_gazebo diff_wheeled_robot_gazebo.launch
- roslaunch diff_wheeled_robot_control keyboard_teleop.launch

Chapter 5. Simulating Robots Using ROS, CoppeliaSim, and Webots

- roscore
- cd dev/coppeliaSim/
- ./coppeliaSim.sh
- rqt_image_view
- rostopic pub /csim_demo/seven_dof_arm/elbow_pitch/cmd std_msgs/Float32 "data: 1.0"
- rostopic echo /csim_demo/seven_dof_arm/elbow_pitch/state
- webots
- rostopic echo /model_name
- rosservice call /e_puck_59313_jcacace_Lenovo_Legion_5_15ARH05/camera/enable "value: true"
- rosrun webots_demo_pkg e_puck_manager
- roslaunch diff_wheeled_robot_control keyboard_teleop.launch