**Building a robot moving it using ros and rpi**

Building the robot: [[Morpheus Chair] Build the Structure of a ROS + Raspberry Pi Robot | Ep.1 - YouTube](https://www.youtube.com/watch?v=TABVZf5vKVA)

Coding the driver module : [[Morpheus Chair] Move DC Motors for a Robot with Raspberry Pi | Ep.2 - YouTube](https://www.youtube.com/watch?v=c6oUR2P3yfI)

Ros part and teleop : [How to build a Raspberry Pi & ROS Camera Robot | Ep.3 - The Construct (theconstructsim.com)](https://www.theconstructsim.com/morpheus-chair-move-robot-and-see-camera-with-ros-in-raspberrypi-episode-3/)

The code base : [theconstructcore / morpheus\_chair — Bitbucket](https://bitbucket.org/theconstructcore/morpheus_chair/src/master/)

Idea

* Everything will run on the rpi
* But we will ssh into the rpi and teleop from there
* List of files to use
  + morpheus\_chair/morpheus\_chair\_pkg/scripts/move\_with\_cmd\_vel.py

**Teleop keyboard ros**

[teleop\_twist\_keyboard - ROS Wiki](http://wiki.ros.org/teleop_twist_keyboard)

* Publishes to topic : cmd\_vel
* Github : [teleop\_twist\_keyboard/teleop\_twist\_keyboard.py at master · ros-teleop/teleop\_twist\_keyboard · GitHub](https://github.com/ros-teleop/teleop_twist_keyboard/blob/master/teleop_twist_keyboard.py)

**What is a h bridge**

[What Is an H-Bridge? (build-electronic-circuits.com)](https://www.build-electronic-circuits.com/h-bridge/)

**Rpi pwm pins**

[rpi pwm pins - Google Search](https://www.google.com/search?q=rpi+pwm+pins&oq=rpi+pwm+&aqs=edge.1.69i57j0i512l6j0i22i30j69i64.3481j0j1&sourceid=chrome&ie=UTF-8)

**Rpi gpio code**

[Raspberry Pi Raspberry Pi Gpio Access | Raspberry Pi (electronicwings.com)](https://www.electronicwings.com/raspberry-pi/raspberry-pi-gpio-access)

**Pwm for motor control**

[Pulse Width Modulation Used for Motor Control (electronics-tutorials.ws)](https://www.electronics-tutorials.ws/blog/pulse-width-modulation.html)