

20160401 installed 12.04 desktop, ros groovy, groovy care-o-bot, pythonviztools
<http://wiki.ros.org/groovy/Installation/Ubuntu>
<http://wiki.ros.org/Robots/Care-O-bot/groovy>

And it worked!

Tab1

```
export ROBOT=cob4-2 //replace with 3-1 //go to bash.rc
export ROBOT_ENV=ipa-apartment ////replace with kitchen//go to bash.rc
roslaunch cob_bringup_sim robot.launch
```

tab2

```
sadie@ann:~$ export ROBOT=cob3-2
sadie@ann:~$ export ROBOT_ENV=ipa-apartment
roslaunch cob_bringup dashboard.launch
```

tab3

```
sadie@ann:~$ export ROBOT=cob3-2
sadie@ann:~$ export ROBOT_ENV=ipa-apartment
sadie@ann:~$ roslaunch cob_bringup rviz.launch //see the sensor data
```

tab4

```
roslaunch cob_navigation_global 2dnav_ros_dwa.launch //load environment map
(roslaunch cob_navigation_global replace with local 20160506)
```

tab 5

```
rostopic echo /scan_front //output of the sensor
Or
rostopic echo /move_base_simple/goal //for tr navigation to see what is going on expo
```

Ub12 terminator:

T1 roslaunch cob_bringup_sim robot.launch

T2 roslaunch cob_bringup dashboard.launch

T3 roslaunch cob_navigation_global 2dnav_ros_dwa.launch

T4 roslaunch cob_bringup rviz.launch (change fixed frame to /map)

T5 rosrun cob_bringup_sim spawn_object.py all

Script server url:

https://github.com/ipa320/cob_command_tools/blob/groovy/cob_script_server/src/simple_script_server.py

agX3-55

Git

Gregouras g.s.h.ac.uk@g Dd12git

<http://answers.ros.org/question/229240/care-o-bot-simulation-fails-on-indigo-ubuntu-1404-all-packages-up-to-date-as-of-20160316/>

With the release version the robot is not moving because there is a conflict with the cmd_vel topic name. The navigation publishes the twist command to /base_controller/command and gazebo is subscribed to /base/twist_controller/command.

The problem is already fixed but, at the moment, you have to use the actual source version. You can create a cob3-2_navigation.rosinstall file with the following lines:

- git:

uri: 'https://github.com/ipa320/cob_common.git'
local-name: cob_common
version: indigo_dev

- git:

uri: 'https://github.com/ipa320/cob_control.git'
local-name: cob_control
version: indigo_dev

- git:

uri: 'https://github.com/ipa320/cob_driver.git'
local-name: cob_driver
version: indigo_dev

- git:

uri: 'https://github.com/ipa320/cob_robots.git'
local-name: cob_robots
version: indigo_dev

```
- git:
  uri: 'https://github.com/ipa320/cob_navigation.git'
  local-name: cob_navigation
  version: indigo_dev
```

And install the necessary packages using the commands:

```
rosinstall ~/YourWorkspace/src cob3-2_navigation.rosinstall
rosdep install --from-path ~/YourWorkspace/src -i -y
source ~/YourWorkspace/devel/setup
```

From email 20160317

The particular solution to your problem is most likely changing the global fixed frame in rviz from map to odom_combined. This is fixed by cloning the current development branches posted in the answer, which change the default rviz config used when doing `roslaunch cob\_navigation\_local rviz.launch`.

The following commands create a workspace which should contain the most up to date development branches. The cob_indigo_bringup rosinstall contains a couple of additional repositories which you probably don't need. At the very least, you need cob_calibration_data, cob_common, cob_control, cob_driver, cob_navigation, cob_robots, and cob_simulation.

```
mkdir -p ~/catkin_ws/src
cd ~/catkin_ws/src
catkin_init_workspace
cd ~/catkin_ws
catkin_make
```

```
wstool init src
cd src
wstool merge
https://raw.githubusercontent.com/ipa320/setup/master/repositories/cob\_indigo\_bringup.rosinstall
wstool update
```

```
rosdep update
rosdep update --from-paths -i -y
catkin_make
```

At the moment the slam navigation also does not work with the base install, but if you checkout the branch fix/deprecated_costmap_params from git@github.com:mig-em/cob_navigation.git, it should work.

```
cd cob_navigation/
git remote add mig-slam git@github.com:mig-em/cob_navigation.git
git fetch mig-slam
git checkout mig-slam/fix/deprecated_costmap_params
cd ~/catkin_ws
```

Catkin_make

Rosrun Rqt_reconfigure Rqt_reconfigure (select base)

roslaunch cob_teleop teleop_keyboard.launch

(roslaunch cob_teleop teleop_keyboard.launch walk_vel:=100)

rostopic echo /base/twiommand_teleop_keyboard

Teleop_keyboard.launch chnages

<param name="walk_vel" value="100" /> changed from 0.1

roslaunch cob_navigation_global 2dnav_ros_tr.launch

rostopic echo /move_base/goal

rostopic echo /move_base/status

roslaunch cob_teleop teleop_keyboard.launch

rostopic echo /base/velocity_smoother/commmd d

roslaunch cob_bringup dashboard.launch

roslaunch cob_bringup_sim robot.launch

roslaunch cob_bringup rviz.launch