

KBSW210712 ROS - teleop_twist_keyboard

teleop_twist_keyboard,

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- - Ubuntu 16.04 X86
 - ROS Kinetic
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- Slamware Slamware
 - Apollo/Ares/Athena
-

ROS-

1.Slamware ROS SDKROS

2.ROS sdsrccatkin_wsROS slamware_ros_samplesrccatkin

```
cd catkin_ws/src
catkin_init_workspace
```

3.

```
cd ..
catkin_make
```

4.

```
source devel/setup.bash
```

5.slamware_ros_sdk_server_node

```
roslaunch slamware_ros_sdk slamware_ros_sdk_server_node.launch ip_address:=10.6.128.141
//APip_address192.168.11.1
```

6.4teleop_twist_keyboard_nodeW/S/A/D///

```
roslaunch slamware_ros_sample teleop_twist_keyboard.launch
```

```
yzx@yzx-Baytrail-Series:~/Desktop/catkin_ws$ roslaunch slamware_ros_sample teleo
p_twist_keyboard.launch
... logging to /home/yzx/.ros/log/9f177ab8-e3bd-11eb-80bb-30b49ecd6bfc/roslaunch
-yzx-Baytrail-Series-24374.log
Checking log directory for disk usage. This may take awhile.
Press Ctrl-C to interrupt
WARNING: disk usage in log directory [/home/yzx/.ros/log] is over 1GB.
It's recommended that you use the 'rosclean' command.

started roslaunch server http://yzx-Baytrail-Series:35216/

SUMMARY
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PARAMETERS
* /rostdistro: kinetic
* /rosversion: 1.12.14

NODES
/
  slamware_ros_sample (slamware_ros_sample/teleop_twist_keyboard.py)

ROS_MASTER_URI=http://localhost:11311

process[slamware_ros_sample-1]: started with pid [24392]

Reading from the keyboard and Publishing to Twist!
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Moving around:
      w
  a    s    d

CTRL-C to quit
```

```
moveBindings = {
    'w': (1.0, 0.0),
    's': (-1.0, 0.0),
    'a': (0.0, 1.0),
    'd': (0.0, -1.0)
}
```

pubtopic

```
pub = rospy.Publisher('/cmd_vel', Twist, queue_size = 1)
```

```
rospy.init_node('teleop_twist_keyboard_node')
```

linearXangularZ

```
key = getKey()
print(key)
if key in moveBindings.keys():
    linearX = moveBindings[key][0]
    angularZ = moveBindings[key][1]
else:
    linearX = 0.0
    angularZ = 0.0
    if (key == '\x03'):
        break
```

topic

```
twist = Twist()
twist.linear.x = linearX
twist.angular.z = angularZ
pub.publish(twist)
```