

ROS demo



CAN CAN

“ ROS ROS2 ROS

- 1. ROS-SDK SDK
- 2.
- 3. source
- 4. CAN-COM HUB CAN
 - susb
- 5. CAN

“



“ ,

demo

- * demo_basic_ctrl.launch
- * demo_key_ctrl.launch

demo_basic_ctrl.launch /cmd_vel

demo_key_ctrl.launch turtle_teleop_key turtlesim turtlesim

“ ,

launch

```
[ INFO] [1714662015.789025136]: xnode_vehicle: Vehicle online
[ INFO] [1714662015.789215455]: xnode_vehicle: CAN mode locked
[ INFO] [1714662016.189858534]: xnode_vehicle: mode OK(CAN mode)
[ INFO] [1714662016.789707014]: xnode_vehicle: Vehicle enable
[ INFO] [1714662016.789779160]: xnode_vehicle: Device type = MARK1_DIFF
[ INFO] [1714662016.789801928]: xnode_vehicle: ### Vehicle init finish ###
[ INFO] [1714662017.290447759]: xnode_vehicle: cal_mode = odom ||| model = Differential
[ INFO] [1714662017.290510966]: xnode_vehicle: track_width = 0.520m ||| wheel_base = 0.410m
[ INFO] [1714662017.290542395]: xnode_vehicle: ### Odom init finish ###
[ INFO] [1714662017.290570052]: xnode_vehicle: ===== VEHICLE READY TO GO =====
```

launch msg src/drivers/xpkg_vehicle/README.md ,

- calc_speed true false false
- mode_can_lock CAI true C false

!!!note mode_can_lock false

- rate_x 1 0.2

lau rostopic list ROS

- /odom nav_msgs/Odometry
- /tf tf2_msgs/TFMessage tf launch
- /cmd_vel geometry_msgs/Twist linear.x / linear.y angular.z

#4

Yunhao Tian 9 2024 07:49:11

Yixuan Jiang 28 2024 12:13:25