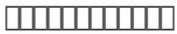


# ROS demo



CAN CAN

“ [ ROS [ROS2](#) [ ROS ] ]



1. [ ROS-SDK ] [ SDK ]
2. [ ]
3. [ ] source
4. [ ] CAN-COM HUB [ ] CAN [ ]
  - [ ] |usb [ ]
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 CAN true C false

!!!note mode\_can\_lock false

- rate\_x 1 0.2

launch 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