

# ROS demo



CAN CAN

“ [ ROS [ROS1](#) ROS2 [ ROS

1. ROS-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