PREREQUISITES

- Install ROS Groovy or later in Ubuntu 12.04 LTS (recommended).

SOFTWARE COMPILATION

- Put all the code in a folder called laser3D.
- Include this folder in the ROS package path:

  $ export ROS_PACKAGE_PATH=/home/user/ros/ros-pkg:/another/path

- Then, open a terminal and go to the folder:

  $ roscd laser3D

- Compile the package with rosmake: comando:

  $ rosmake

- The final output should be somehing like:

```
[rosmake-1] Finished <<< laser3D [PASS] [ 18.24 seconds ]
[ rosmake ] Results:
[ rosmake ] Built 36 packages with 0 failures.
[ rosmake ] Summary output to directory
[ rosmake ] /home/raul/.ros/rosmake/rosmake_output-20130628-174301
raul@PORTATIL:~/fuerte_workspace/laser3D$
```

SOFTWARE EXECUTION

- First, ROS core:

  $ roscore

- Launch the hardware server:

  $ roslaunch laser3D laser3D.launch

- Here, nodes Hokuyo, Dynamixel and Laser3D have been launched. Then, open the client:

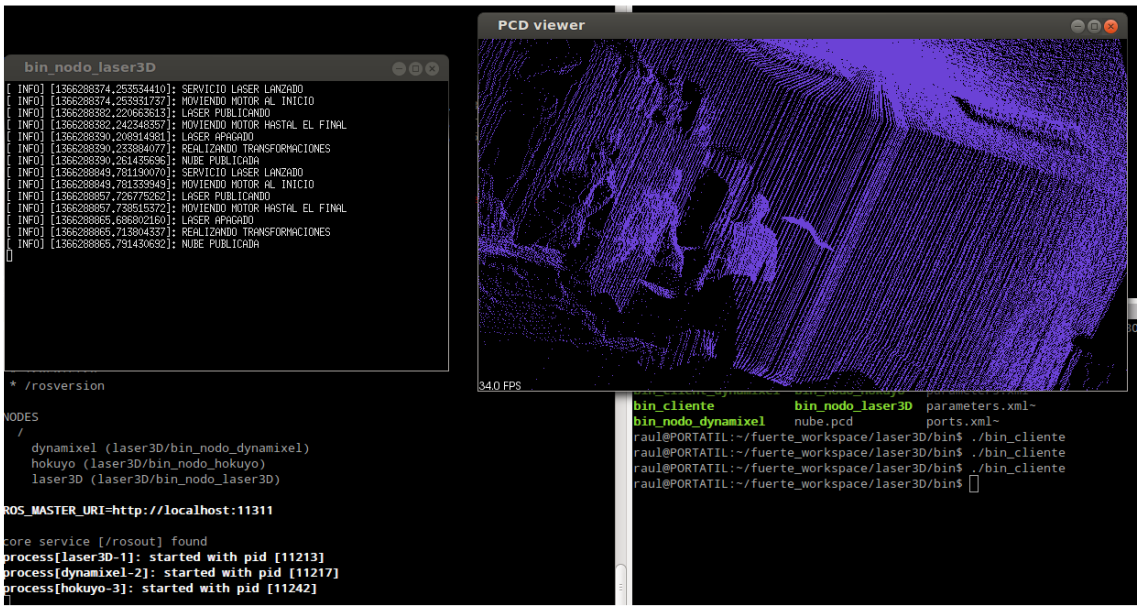
  $ rosrun laser3D bin cliente

- If this does not work, it is because the laser options, given in a xml file, are not being loaded. Then, open manually the binary file:

  $ roscd laser3D

$ cd bin
$ ./bin_cliente

- After all this, the state should be something like this:



Javier V. Gómez

jvgomez@ing.uc3m.es
engjotauve@gmail.com