

Ros Samples

In order to use the Examples bellow you need to build the catkin workspace located under : */home/reetiDevel/Samples/ROS*.

To do that :

- go to the directory mentioned above through command line and use the command : *catkin_make*
- then source the following file : */home/reetiDevel/Samples/Ros/devel/setup.bash*
- you should now be able to run the nodes using the following command : *roslaunch reetirosexamples examplename* (e.g ReetiPose)

The Examples :

- ReetiPose:
 - located on Reeti in */home/reetiDevel/Samples/ROS/src/reetirosexamples*
 - create a ServiceClient and a Subscriber that will connect respectively to the *SetPose* Service and the *GetPosition* Publisher
 - allows to set the position of the motors at a given speed and poll the current position of the motors
- ReetiTalking:
 - located on Reeti in */home/reetiDevel/Samples/ROS/src/reetirosexamples*
 - create a ServiceClient and ServiceServers that will connect respectively to the *SayService*, the *GetBookmark* and the *EndTalking* Services
 - allows to make the Reeti talks and get back information from the bookmarks set up in the text.
- ReetiPlayer:
 - located on Reeti in */home/reetiDevel/Samples/ROS/src/reetirosexamples*
 - create ServiceClients that will connect to the *PlayPose*, *PlaySequence* and *StopCurrentSequence* services.
 - allows to make executes the differents files used by the REETI
- ReetiCamera:
 - located on Reeti in */home/reetiDevel/Samples/ROS/src/reetirosexamples*
 - create ServiceClients that will connect to the *TakePicture*, *RecordVideo* and *StopRecord* services.
 - allows to use the cameras in the Reeti's eyes

Bitbucket repository : [Ros Samples](#)