

ROS2 avec SO-ARM101

ROS2 et MoveIt2

Installer les paquets ROS2 du SO-ARM100 :

- Cloner le paquet dans un workspace ROS2 https://github.com/JafarAbdi/ros2_so_arm100
- Cloner le submodule <https://github.com/TheRobotStudio/SO-ARM100> dans `so_arm100_description/SO-ARM100` (<https://www.freecodecamp.org/news/how-to-use-git-submodules/>)
- Ou simplement :

```
mkdir -p ~/ws_so_arm100/src
cd ~/ws_so_arm100/src
git clone --recurse-submodules https://github.com/JafarAbdi/ros2_so_arm100
cd ~/ws_so_arm100
sudo rosdep init
rosdep update && rosdep install --ignore-src --from-paths src -y
colcon build --symlink-install # dans une VM ajouter --parallel-workers 1
source install/setup.bash
ros2 launch so_arm100_moveit_config demo.launch.py hardware_type:=mock_components #
hardware_type:=real for running with hardware
```

Tester la démo en simulation :

- Lancer un des scripts : https://github.com/JafarAbdi/ros2_so_arm100?tab=readme-ov-file#usage

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