

Instructions for setting up Baxter Simulator in D158

1. Baxter software packages are already installed on the server and a link to those packages needs to be created for our workspace. In a terminal window, type following line:

```
$ source /opt/baxter_ws/devel/setup.bash
```

2. Now, a catkin workspace will be created to overlay Baxter's packages in your home directory:

```
$ mkdir -p ~/baxter_ws/src
$ cd ~/baxter_ws/src
$ catkin_init_workspace
```

```
$ cd ~/baxter_ws/
$ catkin_make
```

3. Add source command for this catkin workspace to your .bashrc file:

```
$ echo "source ~/baxter_ws/devel/setup.bash" >> ~/.bashrc
$ source ~/.bashrc
```

4. To verify this worked:

```
$ echo $ROS_PACKAGE_PATH
```

Verify that you see at least the following 3 paths: **/opt/ros/kinetic/share**, **/opt/baxter_ws/src** and **~/baxter_ws/src**

5. Now copy the Baxter shell script to your catkin workspace:

```
$ cp /opt/baxter_ws/src/baxter/baxter.sh ~/baxter_ws/.
```

6. Use the command **ls -la** to check whether the file is executable. To make the file executable:

```
$ chmod +x ~/baxter_ws/baxter.sh
```

7. For every terminal window you open for Baxter Simulator:

```
$ cd ~/baxter_ws (you should be in your baxter_ws directory)
```

```
$ ./baxter.sh sim
```

Then look for the prompt to change to:

```
[baxter - http://localhost:11311] <user>@<computer>:~/baxter_ws$
```

7. To start the Baxter Simulator in Gazebo:

```
$ roslaunch baxter_gazebo baxter_world.launch
```

Now you can try all of the commands for Baxter Simulator in Chapter 6 of ROS Robotics By Example!