

Polaris GEM e2 ROS Workspace Initialization & Setup

~/.bashrc file configuration (YOU SHOULD NOT MODIFY THIS FILE)

The ~/.bashrc file is configured as follows:

```
##### GEM Setup #####
export PLM_LICENSE=~/licenses
export platform_name=white_e2

##### ROS Setup #####

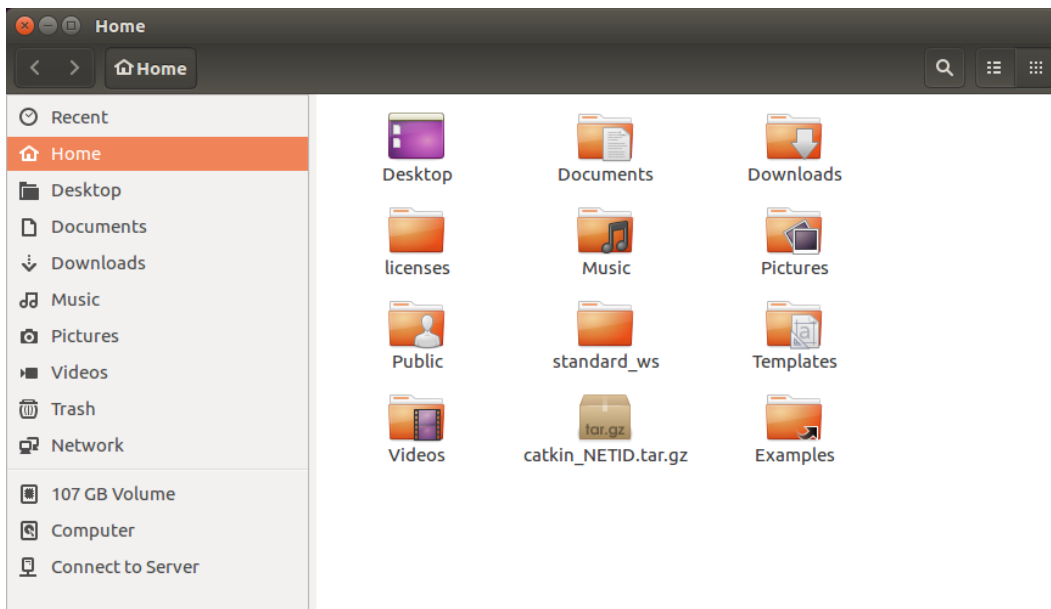
export ROS_DISTRO=kinetic
source /opt/ros/kinetic/setup.bash

##### CUDA Setup #####

export PATH=/usr/local/cuda-9.0/bin${PATH:+:${PATH}}
export LD_LIBRARY_PATH=/usr/local/cuda-9.0/lib64\{LD_LIBRARY_PATH:+:${LD_LIBRARY_PATH}}
```

Project Catkin Workspace Initialization

Extract catkin_NETID.tar.gz file to /home/dev/ and change the NETID to your NETID or project name.



```
$ cd catkin_yourNETID
```

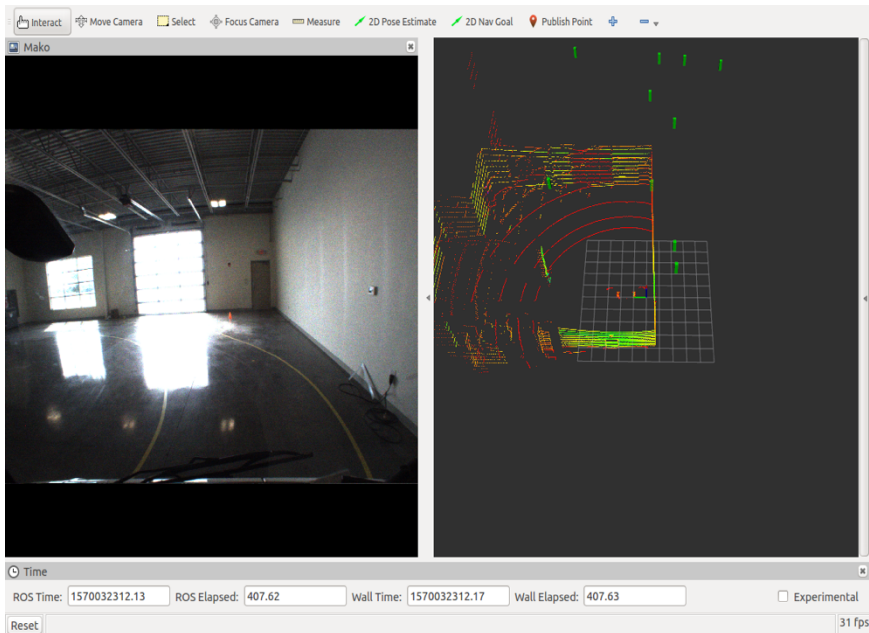
```
$ catkin build
```

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

Launch Sensor Visualization & DBW Joystick Demo

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

```
$ roslaunch basic_launch visualization.launch
```



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

```
$ roslaunch basic_launch visualization.launch
```

```
/home/dev/standard_ws/src/basic_launch/launch/dbw_joystick.launch http://localhost:11311
/home/dev/standard_ws/src/basic_launc... x dev@dev-gem: ~/standard_ws x
NODES
 /game_control/
   joy (joy/joy_node)
   pacmod_game_control (pacmod_game_control/pacmod_game_control_node)
 /pacmod/
   kvaser_can_bridge (kvaser_interface/kvaser_can_bridge)
   pacmod (pacmod/pacmod)

auto-starting new master
process[roscpp]: started with pid [16796]
ROS_MASTER_URI=http://localhost:11311

setting /run_id to abf1d6a2-ebda-11e9-933a-78d00423958e
process[rosout-1]: started with pid [16809]
started core service [/rosout]
process[game_control/joy-2]: started with pid [16824]
process[game_control/pacmod_game_control-3]: started with pid [16827]
process[pacmod/kvaser_can_bridge-4]: started with pid [16836]
process[pacmod/pacmod-5]: started with pid [16854]
[ INFO ] [1570766003.915183952]: Kvaser CAN Interface - Got hardware_id: 11783
[ INFO ] [1570766003.916812455]: Kvaser CAN Interface - Got can_circuit_id: 0
[ INFO ] [1570766003.918647142]: Kvaser CAN Interface - Got bit_rate: 500000
[ERROR] [1570766003.980361689]: Couldn't open joystick force feedback!
```

Note: DON'T worry about this [ERROR], this is indeed an [WARNING]. Everything will work as designed. Now, you can control the GEM using the game controller.