```bash
1  #!/bin/bash
2  #ENCODING: UTF-8
3  #Created by Jordi Hortal v1.2
4  AUTO=false
5  if [ $# -eq 0 ]; then
6      read -p "Start as: master or slave? " SCRIPT
7  elif [ $# -eq 1 ]; then
8      SCRIPT="$1"
9  elif [ $# -eq 3 ]; then
10     SCRIPT="$1"
11     MASTER="$2"
12     SLAVE="$3"
13     AUTO=true
14 else
15     echo "$(tput setaf 1)Incorrect parameters$(tput sgr 0)"
16     exit 1
17 fi
18
19 echo "Creating configuration as $SCRIPT"
20 if [ "$SCRIPT" = "master" ]; then
21     #read -p "ip of the PC or master: " MESTRE
22     #MESTRE=192.168.1.100
23     MESTRE=$(ifconfig wlan0 | grep 'inet addr:' | grep -v '127.0.0.1' | cut -d: -f2 |
         awk '{ print $1}')
24     if [ "$MESTRE" = "" ]; then
25         MESTRE=$(ifconfig wlan0 | grep 'inet:' | grep -v '127.0.0.1' | cut -d: -f2 |
             awk '{ print $1}')
26         if [ "$MESTRE" = "" ]; then
27         echo "$(tput setaf 1)ERR: No internet conection detected$(tput sgr 0)"
28         exit 1
29         fi
30     fi
31     #depenent del pc pot ser inet o inet addr
32
33     echo "ip of the PC or master: $MESTRE"
34     export ROS_HOSTNAME=$MESTRE
35     export ROS_MASTER_URI=http://$MESTRE:11311
36     sleep 1
37
38     roscore&
39     sleep 2
40     #rosparam set joy_node/dev "/dev/input/js1"
41     #Si dona error en el joynode llavors has de mirar en quin js# s'ha posat
42     rosrun joy joy_node&
43     rosrun joy2twist joy2twist.py&
44     sleep 1
45
46     read -p "$(tput setaf 4)Do you want to connect to a robot remotely (yes/no):
         $(tput sgr 0) " SSH
47     ERR=true
48     if [ $SSH = "s" ] || [ $SSH = "si" ] || [ $SSH = "SI" ] || [ $SSH = "S" ] ||
         [ $SSH = "yes" ] || [ $SSH = "y" ]; then
49         echo "$(tput setaf 4)Select remote direction"
50         echo "1) BigBot"
51         echo "2) Jordi acer"
52         echo "3) arlab Asus"
53         echo "4) new...$(tput sgr 0)"
54         while [ $ERR != "false" ]
55         do
56         read NUM
```

```
57          case $NUM in
58              1)  USER="mobilerobot"
59                  HOST="192.168.1.101"
60                  ERR=false
61                  ;;
62              2)  USER="jordi"
63                  HOST="192.168.1.146"
64                  ERR=false
65                  ;;
66              3)  USER="arlab"
67                  HOST="192.168.1.100"
68                  ERR=false
69                  ;;
70              4)  read -p "Introduce IP: " HOST
71                  read -p "Introduce name of the user: " USER
72                  ERR=false
73                  ;;
74              *)  echo "$(tput setaf 1)ERR: wrong select$(tput sgr 0)"
75          esac
76          done
77
78          USER_HOST="$USER@$HOST"
79          gnome-terminal -e ./inici_remot.exp\ $USER_HOST\ $MESTRE\ $HOST\ 0
80          sleep 1
81
82          rosrun image_view image_view image:=/axis/image_raw                        ⏎
              _image_transport:=compressed &
83          sleep 2
84          rosrun image_view image_view image:=/camera/rgb/image_color                ⏎
              _image_transport:=compressed &
85          sleep 10
86
87          read -p "Vols iniciar stream_d'audio? (s/n)" AUDIO
88
89          if [ $AUDIO = "s" ]; then
90              ./stream_audio.sh\ $MESTRE\ $ESCLAU\ $USER_HOST
91          elif [ $AUDIO = "n" ];then
92              exit 0
93          else
94              echo "$(tput setaf 1)ERR: Wrong type"
95              echo "Pots iniciar manualment l'stream amb sh stream_audio.sh$(tput sgr  ⏎
                0)"
96              exit 1
97          fi
98
99      else
100         exit 1
101     fi
102
103 elif [ "$SCRIPT" = "slave" ]; then
104     if [ $AUTO = "true" ]; then
105         MESTRE="$MASTER"
106         ESCLAU="$SLAVE"
107     else
108         read -p "ip of the PC or master: " MESTRE
109         read -p "ip of the robot or slave: " ESCLAU
110     fi
111
112     export ROS_HOSTNAME=$ESCLAU
113     export ROS_MASTER_URI=http://$MESTRE:11311
114     gnome-terminal --title "kinect" -x bash -c "roslaunch openni_launch openni.launch  ⏎
```

```sh
115        sleep 2
116
117        echo "executa rosrun project bigbot"
118        rosrun projectbigbot base_controller &
119        sleep 3
120        export ROS_NAMESPACE=axis
121        rosrun axis_camera axis.py _hostname:=axis-00408cac2fb4.local _password:=ferran &
122
123        echo "executa rosrun axis_camera"
124        sleep 3
125        avconv -f alsa -i hw:0,0 -acodec libmp3lame -ab 32k -ar 14500 -re -f rtp      ⏎
             rtp://234.5.0.5:1234
126        echo "enviant audio per rtp:234.5.0.5:1234"
127        sleep 2
128        exit 0
129 else
130        echo "$(tput setaf 1)ERR: Wrong type$(tput sgr 0)"
131        exit 1
132 fi
133 echo "$(tput setaf 2)Configurate as $SCRIPT. End program. $(tput sgr 0)"
134 #printf "es com echo pero sense fer un \n"
135 #roscore
136 #rosnode kill audio_play
137 #rosrun audio_capture audio_capture
138 #rosnode kill audio_capture
139 #rosrun audio_play audio_play
140 #gnome-terminal --title "rosrun axis_camera" -x bash -c "rosrun axis_camera axis.py  ⏎
      _hostname:=axis-00408cac2fb4.local _password:=ferran "&
141 exit 0
142
```