

# Writing Gazebo Plugins

This section will cover how to write gazebo plugins and how to integrate them with ROS. There are a number of tutorials online as well as examples in the robosub simulator repo but it can all be a little hard to find. Thus I'll mostly just be gathering all the resources here and giving a few tips.

For an overview of writing gazebo plugins see [here](#).

To see how ROS integration works with gazebo plugins go [here](#).

The best resource to see examples of gazebo plugins in action is our [robosub\\_simulator](#) repo, especially these files:

- [Thruster Plugin](#)
- [Model and World Plugin Examples](#)

A couple things to note when working with plugins:

- Your GAZEBO\_PLUGIN\_PATH must contain the path where your plugins are compiled to. By default compiled libraries are put in your ros\_workspace/devel/lib folder. This path (and others) are set up in the simulator repo's [package.xml](#).
- Gazebo does not automatically reload plugins when they are recompiled. Unfortunately this means you will have to restart gazebo every time you make a change.
- The update loop of the plugin (setup [here](#) and defined [here](#)) is run every single frame (50+ times/second) so make sure it is optimized.

From:

<https://robosub.eecs.wsu.edu/wiki/> - **Palouse RoboSub Technical Documentation**

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Last update: **2016/12/16 12:18**

