

# Two\_loggers

double\_logger\_control\_pe.  
launch

loggers\_gazebo/launch/  
double\_logger\_world\_pe.launch

创建世界

loggers\_gazebo/worlds/wall\_double.world

添加机器人模型

loggers\_description/urdf/double\_logger\_pe0.  
urdf.xacro

loggers\_description/urdf/double\_logger\_pe1.  
urdf.xacro

loggers\_description/urdf/logger\_p.urdf.  
xacro

loggers\_description/urdf/logger.urdf.xacro

loggers\_description)/urdf/materials.xacro

loggers\_description)/urdf/materials.xacro

在materials.xacro命名颜色

```
<arg name="narrow" default="false"/>  
<arg unless="$(arg narrow)"  
name="sim_world_name" value="wall_double"/>
```

其中，wall\_double为无墙；wall\_narrow\_exit是有墙的

将value="wall\_double"修改成value="wall\_narrow\_exit"即变成有墙的环境

通过修改<real\_time\_factor>和<real\_time\_update\_rate>可以改变仿真速度

```
<real_time_factor>1</real_time_factor>  
<real_time_update_rate>1000</real_time_update_rate>
```

```
调用插件 <plugin name="differential  
drive_controller" filename="  
libgazebo_ros_diff_drive.so">
```