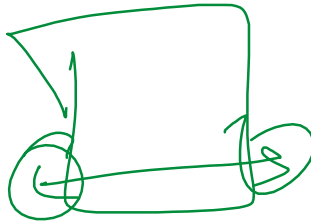


Gazebo Plugins for Ros

Control

```
<gazebo>
  <plugin filename="libgazebo_ros_diff_drive.so" name="gazebo_base_controller">
    <odometry_frame>odom</odometry_frame>
    <commandTopic>cmd_vel</commandTopic>
    <publish_odom>true</publish_odom>
    <publish_odom_tf>true</publish_odom_tf>
    <update_rate>15.0</update_rate>
    <left_joint>wheel_left_joint</left_joint>
    <right_joint>wheel_right_joint</right_joint>
    <wheel_separation>0.8</wheel_separation>
    <wheel_diameter>0.3</wheel_diameter>
    <max_wheel_acceleration>0.7</max wheel_acceleration>
    <robotBaseFrame>base</robotBaseFrame>
  </plugin>
</gazebo>
```



cmd_vel

