1 通过ssh远程连接到Jackl

2 输入rosrun jackal\_base calibrate\_compass

3 Jackal应该在原地缓慢旋转60秒，记录磁强计数据

4 然后输出

Started rosbag record, duration 60 seconds, pid [6793]

Started motion commands, pid [6794]

[ INFO] [1417463864.452760841]: Subscribing to /tf

[ INFO] [1417463864.457840117]: Subscribing to /imu/rpy/raw

[ INFO] [1417463864.462399042]: Subscribing to /imu/data\_raw

[ INFO] [1417463864.466624735]: Subscribing to /imu/mag

[ INFO] [1417463864.474944762]: Recording to /tmp/calibrate\_compass.xxxx/imu\_record.bag.

Test underway.

Time remaining: 0

Shutting down motion command publisher.

Waiting for rosbag to shut down.

Computing magnetic calibration.

Calibration generated in /tmp/calibrate\_compass.g8oM/mag\_config.yaml.

Restart ROS service to begin using saved calibration.

5 完成后，提示Copy calibration to /opt/ros/indigo/etc/jackal\_base? [Y/n] 选y系统将提示您输入用户密码，以便将新校准保存到$ros\_etc\_dir。

6 完成后，重新启动ROS服务以开始使用新的校准：

sudo service ros restart

当第一次接收到Jacal时，以及通过添加新外围设备修改平台时，应执行校准。作为季节性维护的一部分，建议每年重新校准一次。