launch/lab3.launch

```
<?xml version="1.0"?>
<launch>
  <!-- Bring up all local nodes first -->

  <!-- model to visualize the Turtlebot3 in RVIZ -->
  <!-- <include file="$(find turtlebot3_bringup)/launch/turtlebot3_model.launch"/> -->

  <!-- controller to rotate the robot -->
  <node
    name="controller" pkg="lab3" type="turtlebot_controller.py"
    output="screen" launch-prefix="xterm -e"
  />

  <!-- mouse controller -->
  <node
    name="mouse" pkg="lab3" type="mouse_client_OO.py"
    launch-prefix="xterm -e"
  />

  <!-- remote nodes -->
  <machine
    name="robot5"
    address="robot5"
    env-loader="/home/pi/robot_ws/devel/remote_env_loader.sh"
    default="true"
    user="pi"
  />

  <!-- core functionality of the Turtlebot3 -->
  <node machine="robot5" pkg="rosserial_python" type="serial_node.py"
name="turtlebot3_core" output="screen">
    <param name="port" value="/dev/ttyACM0"/>
    <param name="baud" value="115200"/>
  </node>

  <!-- lidar functionality of the Turtlebot3 -->
  <arg name="set_frame_id" default="base_scan"/>
  <node machine="robot5" pkg="ld08_driver" type="ld08_driver" name="turtlebot3_lds"
output="screen" args="LD08">
    <param name="frame_id" value="$(arg set_frame_id)"/>
  </node>

</launch>
```