## launch/lab3.launch

```
<?xml version="1.0"?>
<launch>
  <!-- Bring up all local nodes first -->
  <!-- model to visualize the Turtlebot3 in RVIZ -->
  <!-- <include file="$(find turtlebot3 bringup)/launch/turtlebot3 model.launch"/> -->
  <!-- controller to rotate the robot -->
  <node
    name="controller" pkg="lab3" type="turtlebot controller.py"
    output="screen" launch-prefix="xterm -e"
  />
  <!-- mouse controller -->
    name="mouse" pkg="lab3" type="mouse client 00.py"
    launch-prefix="xterm -e"
  />
  <!-- remote nodes -->
  <machine
    name="robot5"
    address="robot5"
    env-loader="/home/pi/robot ws/devel/remote env loader.sh"
    default="true"
    user="pi"
  />
  <!-- core functionality of the Turtlebot3 -->
<node machine="robot5" pkg="rosserial_python" type="serial_node.py"
name="turtlebot3_core" output="screen">
    <param name="port" value="/dev/ttyACM0"/>
    <param name="baud" value="115200"/>
  </node>
  <!-- lidar functionality of the Turtlebot3 -->
  <arg name="set frame id" default="base scan"/>
  <node machine="robot5" pkg="ld08 driver" type="ld08 driver" name="turtlebot3 lds"</pre>
output="screen" args="LD08">
    <param name="frame id" value="$(arg set frame id)"/>
  </node>
</launch>
```

1 of 1 3/15/23, 21:58