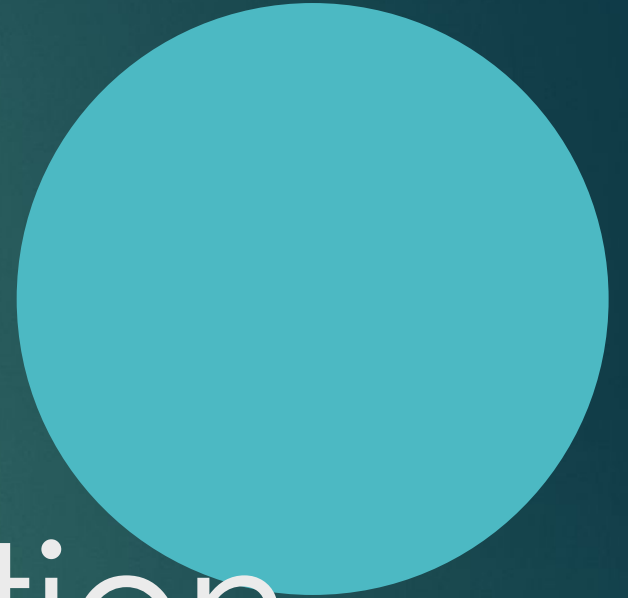# Robot_Localization

in Robot Localization packages:-
make a launch file (robot.launch.py) to memic (dual_ekf_navsat_example.launch.py) with some edits
make your parameter file (robot.yaml) to subscribe to a wheel odometry topic named
/odometry/wheel that publishes a linear x velocity and an angular z velocity, and a gps topic named
/fix that would be the input to navsat_transform_node.

robot_localization Docuoment
http://docs.ros.org/en/melodic/api/robot_localization/html/index.html

Low Speed Self-driving Vehicles- ITI

# Instructors repo Link:

1- https://github.com/ahmedgharieb1
2- https://github.com/M-abdeen

Material repo :
https://github.com/ahmedgharieb1/ITI_LSV_ROS2