

# Planning 2

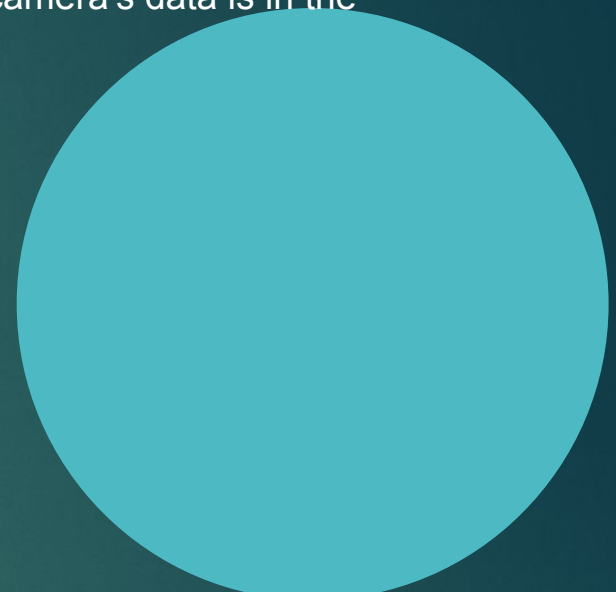
## *(Robot Operating System)*



- 1- create parameters file with name my\_robot\_params.yaml and change launch files to load this parameters file.
- 2- Adjust parameters to make planning stop at 2m away from goal with any given goal orientation.
- 3- Adjust local costmap so that it would take in the camera's data rather than the lidar data. **Hint:** The camera's data is in the following topic /intel\_realsense\_r200\_depth/points.
- 4- Increase local costmap size to 5\*5
- 5- Increase robot's linear velocity to 0.30 m/s Hint: This effect should cause changes to 2 variables.

useful link:-

<https://navigation.ros.org/configuration/packages/configuring-costmaps.html?highlight=costmap>



## Instructors repo Link:

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

Material repo :

[https://github.com/ahmedgharieb1/ITI\\_LSV\\_ROS2](https://github.com/ahmedgharieb1/ITI_LSV_ROS2)

Presentation Link:

[https://docs.google.com/presentation/d/1DIPY0f9PwsUyCdCu\\_e1ouR1yikDMACIWeHKN1df2qO0/edit#slide=id.gd124c8ff8e\\_0\\_0](https://docs.google.com/presentation/d/1DIPY0f9PwsUyCdCu_e1ouR1yikDMACIWeHKN1df2qO0/edit#slide=id.gd124c8ff8e_0_0)

