Perception Lab 1

Using Simulation_demo & teleop_twist_keyboard packages, Create a seperate ROS node that override teleop_twist_keyboard output commands to prevent collisions in forward directions using lidar data.

Note that Gazebo simulator expects command velocity topic named: cmd_vel.

Tune your parameters as much as you can to ensure the following:

- The robot is never stuck.
- No forward collisions happen.

Steps:

- ros2 launch simulation_demo magni_house.launch.py
- ros2 run teleop_twist_keyboard teleop_twist_keyboard cmd_vel:=key_cmd_vel
- python3 override_cmd.py **(You should implement this node)**