Prerequisite:

-install ros2

-run `sudo usermod -a -G dialout` **and restart pc.**

1- Create a ros2 workspace

```
mkdir -p ~/ros2_ws/src
cd ~/ros2_ws/src
```

2- Source ros2 setup for the workspace (so you can run ROS2 commands):

a. Open bashsrc file

```
nano  ~/.bashsrc
```

b. Source ROS2 for the os terminals by adding this line in the end (don't forget to save)

```
source /opt/ros/foxy/setup.bash
```

3- Clone the package into the src file

```
git clone https://github.com/Slamtec/sllidar_ros2.git
```

4- Go back to the workspace

```
cd ~/ros2_ws
```

5- confirm workspace build (ig each time you edit the ws u write this)

```
colcon build --symlink-install
```

6- Source the setup file (this time the workspace file not the ros2 setup file)

```
source install/setup.bash
```

Note: If you don't want having to source the workspace each time then access the bashrc file and write this at the end:

```
Source  ~/<work space name>/install/setup.bash
```

After this make sure to run the basrc file (source it):

```
source ~/.bashrc
```

7- Go back to workspace root and run the command

```
ros2 launch sllidar_ros2 view_sllidar_a3_launch.py
```

https://github.com/ros2/cartographer_ros/blob/ros2/README.rst

https://google-cartographer-ros.readthedocs.io/en/latest/compilation.html#building-installation

https://github.com/Adlink-ROS/neuronbot2/blob/humble/README.md

THIS https://github.com/Slamtec/rplidar_ros