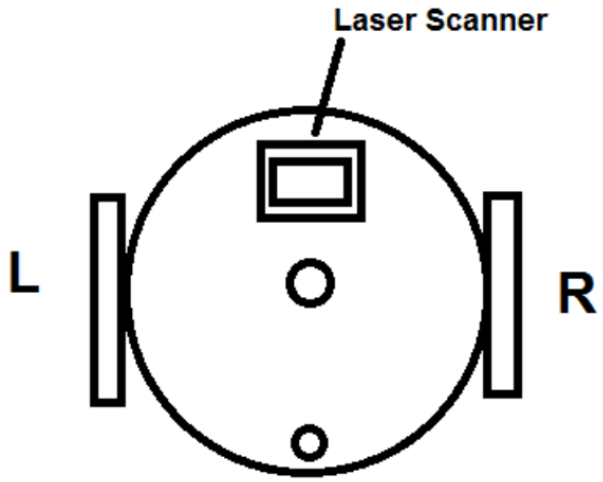
Obstacle Avoidance Using ROS and Gazebo



1. Create a URDF model of the above differential drive robot
2. Simulate the designed robot in Gazebo
3. Add Laser scanner on the top of the robot
4. Create a ROS node to perform obstacle avoidance using the values from the laser scanner

Implementation details

1. Write the code in both cpp and python
2. Design using gui as well as xacro