explore.xml  
  
<launch>  
  <node pkg="explore" type="explore" respawn="false" name="explore" output="screen" >  
    <rosparam file="$(find explore\_beego)/config/costmap\_common.yaml" command="load" ns="explore\_costmap" />  
    <rosparam file="$(find explore\_beego)/explore/explore\_costmap.yaml" command="load" />  
  
    <param name="potential\_scale" value="0.005"/>  
    <param name="orientation\_scale" value="0.0"/>  
**<param name="gain\_scale" value="1.0"/>**    <param name="close\_loops" value="false"/>  
  </node>  
</launch>  
-----------------------------------------------------------------------  
  
  
config/config\_common.yaml  
  
map\_type: costmap  
transform\_tolerance: 0.5  
obstacle\_range: 2.5  
max\_obstacle\_height: 2.0  
raytrace\_range: 3.0  
inscribed\_radius: 0.385  
circumscribed\_radius: 0.685  
inflation\_radius: 0.6  
cost\_scaling\_factor: 15.0  
lethal\_cost\_threshold: 100  
  
observation\_sources: base\_scan  
  
base\_scan: {sensor\_frame: laser, data\_type: LaserScan,  
expected\_update\_rate: 0.2, topic: scan,  
  observation\_persistance: 0.0, marking: true, clearing: true}  
  
-----------------------------------------------------------------------  
explore/Explore\_costmap.yaml  
  
explore\_costmap:  
  global\_frame: /map  
  robot\_base\_frame: base\_link  
  update\_frequency: 1.0  
  publish\_frequency: 0.0  
  raytrace\_range: 5.0  
  obstacle\_range: 5.0  
  static\_map: false  
  rolling\_window: false  
**width: 46.0  
  height: 30.0**  resolution: 0.2  
  **origin\_x: -30.0  
  origin\_y: -30.0**  
  track\_unknown\_space: true