1. 先安装依赖

sudo apt-get install ros-melodic-kobuki-\*

sudo apt-get install ros-melodic-ecl-streams

sudo apt-get install libusb-dev

sudo apt-get install libspnav-dev

sudo apt-get install ros-melodic-joystick-drivers

sudo apt-get install bluetooth

sudo apt-get install libbluetooth-dev

sudo apt-get install libcwiid-dev

sudo apt-get install ros-melodic-bfl

1. gmapping
2. 在编译ROS导航包是提示缺少SDL/SDL\_image.h:

sudo apt-get install libsdl-image1.2-dev

1. Failed to load nodelet '/cmd\_vel\_mux` of type `yocs\_cmd\_vel\_mux/CmdVelMuxNodelet`
2. [FATAL] [1663127531.327839238]: Failed to load nodelet '/navigation\_velocity\_smoother`

sudo apt-get install ros-melodic-yocs-velocity-smoother

1. ROS Failed to create the dwa\_local\_planner/DWAPlannerROS planner

sudo apt-get install ros-melodic-dwa-local-planner

sudo apt-get install ros-melodic-global-planner

1. 安装fake\_localization， 用于仿真环境中的虚拟定位，兼容AMCL输出

sudo apt-get install ros-melodic-fake-localization

1. Warning: Invalid argument “/map“ passed to canTransform argument target\_frame in tf2 frame\_ids···

melodic系统下,将package-name/config文件夹内所有的global\_costmap\_params.yaml和local\_costmap\_params.yaml文件里的头几行去掉“/”,返回工作空间根目录下重新编译。具体原因是tf和tf2迁移问题，可参考 <http://wiki.ros.org/tf2/Migration>