

* Only for simulation mode

Message format:

Configuration these parameters should be send in the nested format, for example if you want to update one parameter, you should sent the complete json Note: Could be changed in future versions

```
interface:
  can0:
    arbitration_id:
      battery:
        id: 769      # Hexadecimal: 301 | Decimal: 769
      kill:
        id: 19       # Hexadecimal: 13  | Decimal: 19
        kill_msg: 0
        release_msg: 1
      control:
        id: 580       # Hexadecimal: 244 | Decimal: 580
        steering_max: 127 #0-127
        throttle_max: 127 #0-127
        throttle_turn_sensitivity: 0.5 # 0-1
        steering_turn_sensitivity: 0.9 # 0-1
        steering_sensitivity: 0.6 # 0-1
        throttle_sensitivity: 0.8 # 0-1
  ros2:
    max_x: 1
    max_z: 1
    x_sensitivity: 0.9
    z_sensitivity: 0.6
    x_turn_sensitivity: 0.4
    z_turn_sensitivity: 0.9

navigation:
  geofence:
    active: True
  visual:
    active: True
  waypoints:
    active: True
    step_xy: 10      #in meters
    proxy_radi: 1
    basing_proxy_radi: 1
    bearing_tol: 10
    crawl_dist: 5     # should be less than equal to step_xy
    no_move_dist: 100
```

Twist cmd_vel_out message format

```
{ "linear":
  { "x": 0.0,
    "y": 0.0,
    "z": 0.0 },
  "angular":
```