

slam_toolbox mapping

This lesson uses the Raspberry Pi as an example.

For Raspberry Pi and Jetson-Nano boards, you need to open a terminal on the host computer and enter the command to enter the Docker container. Once inside the Docker container, enter the commands mentioned in this lesson in the terminal. For instructions on entering the Docker container from the host computer, refer to **[01. Robot Configuration and Operation Guide] -- [4.Enter Docker (For JETSON Nano and RPi 5)]**.

For RDKX5 and Orin boards, simply open a terminal and enter the commands mentioned in this lesson.

1. Introduction to slam-toolbox

slam-toolbox is an open-source 2D SLAM (Simultaneous Localization and Mapping) algorithm package based on ROS. It is primarily used for mapping and localization of mobile robots in unknown environments. Based on the Graph Optimization framework, it combines sensor data from laser lidar (such as 2D LiDAR) and inertial measurement units (IMUs) to construct a 2D grid map of the environment and update the robot's position and pose in real time.

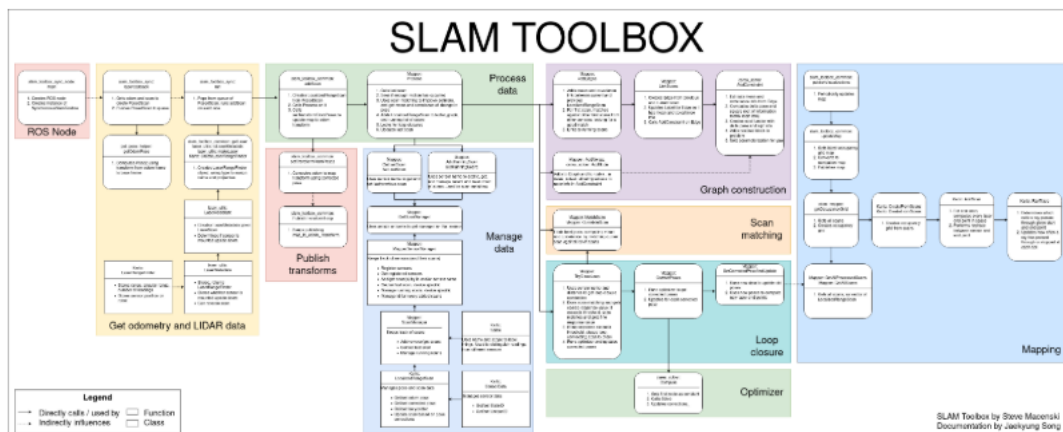
1.1 Core Technology Principles

1.1.1 Front-end Processing (Laser Scan Matching)

- **GICP Algorithm:** Estimates the robot's relative pose change by iteratively calculating the optimal match between the current laser scan and the map. Compared to traditional ICP, GICP introduces a probabilistic model, making it more robust to outliers.
- **Motion Compensation:** Utilizes IMU data to compensate for laser scan distortion during robot motion, improving matching accuracy in dynamic environments.

1.1.2 Back-end Optimization (Graph Optimization)

- **Pose Graph Construction:** Constructs a graph structure from the robot's pose nodes and the relative pose constraints obtained from scan matching.
- **Global Optimization:** Optimizes the pose graph using a nonlinear optimization algorithm (such as the Ceres Solver) to eliminate accumulated errors and achieve global consistency of the map.



GitHub Project Address: https://github.com/SteveMacenski/slam_toolbox

2. Program Functionality

After running the program, the map creation interface will appear in rviz. Use the keyboard or gamepad to control the robot's movements until the map is created. Then run the save map command to save the map.

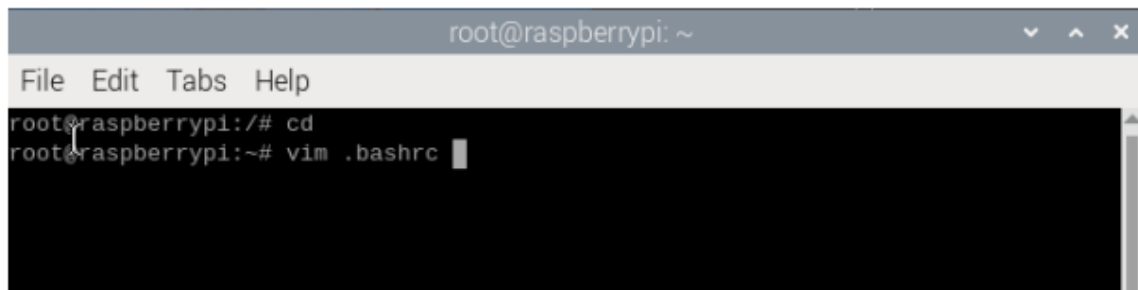
3. Pre-Use Configuration

This robot is equipped with a USB camera, a depth camera, and two different types of lidar. However, since it cannot automatically identify the robot, you need to manually set the robot type and lidar model.

For Raspberry Pi and Jetson-Nano boards, you need to enter the Docker container first. For RDKX5 and Orin controllers, this is not necessary.

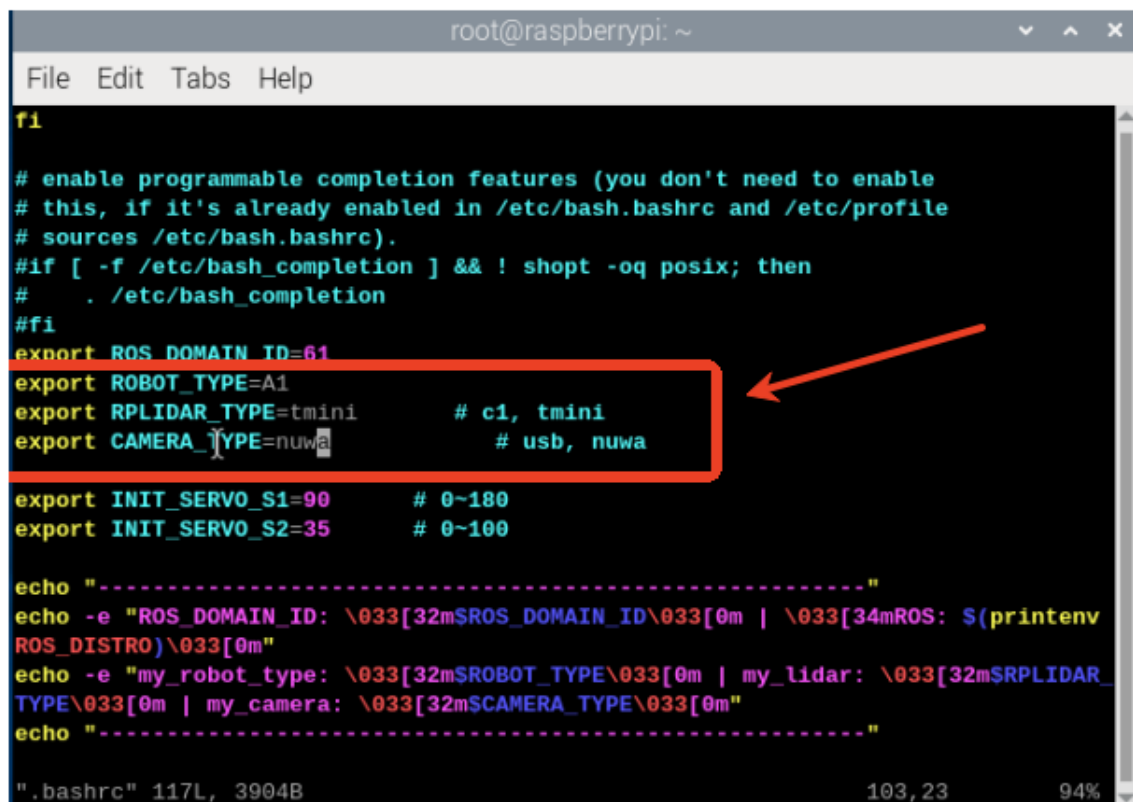
Change the following settings based on the car model, lidar type, and camera type.

```
root@ubuntu:/# cd
root@ubuntu:~# vim .bashrc
```



```
root@raspberrypi: ~
File Edit Tabs Help
root@raspberrypi:/# cd
root@raspberrypi:~# vim .bashrc
```

Find this location and press i on your keyboard to change the settings to the corresponding camera and lidar models. The default settings are tmini and nuwa.



```
root@raspberrypi: ~
File Edit Tabs Help
f1
# enable programmable completion features (you don't need to enable
# this, if it's already enabled in /etc/bash.bashrc and /etc/profile
# sources /etc/bash.bashrc).
#if [ -f /etc/bash_completion ] && ! shopt -oq posix; then
#   . /etc/bash_completion
#fi
export ROS_DOMAIN_ID=61
export ROBOT_TYPE=A1
export RPLIDAR_TYPE=tmini          # c1, tmini
export CAMERA_TYPE=nuwa           # usb, nuwa

export INIT_SERVO_S1=90           # 0~180
export INIT_SERVO_S2=35           # 0~100

echo "-----"
echo -e "ROS_DOMAIN_ID: \033[32m$ROS_DOMAIN_ID\033[0m | \033[34mROS: $(printenv
ROS_DISTRO)\033[0m"
echo -e "my_robot_type: \033[32m$ROBOT_TYPE\033[0m | my_lidar: \033[32m$RPLIDAR_
TYPE\033[0m | my_camera: \033[32m$CAMERA_TYPE\033[0m"
echo "-----"

".bashrc" 117L, 3904B                                103, 23          94%
```

After completing the changes, save and exit vim, then execute:

```
root@raspberrypi:~# source .bashrc
```

```
-----  
ROS_DOMAIN_ID: 61 | ROS: humble  
my_robot_type: M1 | my_lidar: tmini | my_camera: nuwa  
-----
```

```
root@raspberrypi:~#
```

```
root@raspberrypi:~# source .bashrc  
-----  
ROS_DOMAIN_ID: 61 | ROS: humble  
my_robot_type: A1 | my_lidar: tmini | my_camera: nuwa  
-----  
root@raspberrypi:~#
```

4. Program Startup

4.1. Startup Commands

For Raspberry Pi and Jetson-Nano boards, you need to enter the Docker container first. For RDKX5 and Orin controllers, this is not necessary.

Enter the Docker container (see [Docker course] --- [4. Docker Startup Script] for steps).

All the following commands must be executed within the same Docker container (see [Docker course] --- [3. Docker Submission and Multi-Terminal Access] for steps).

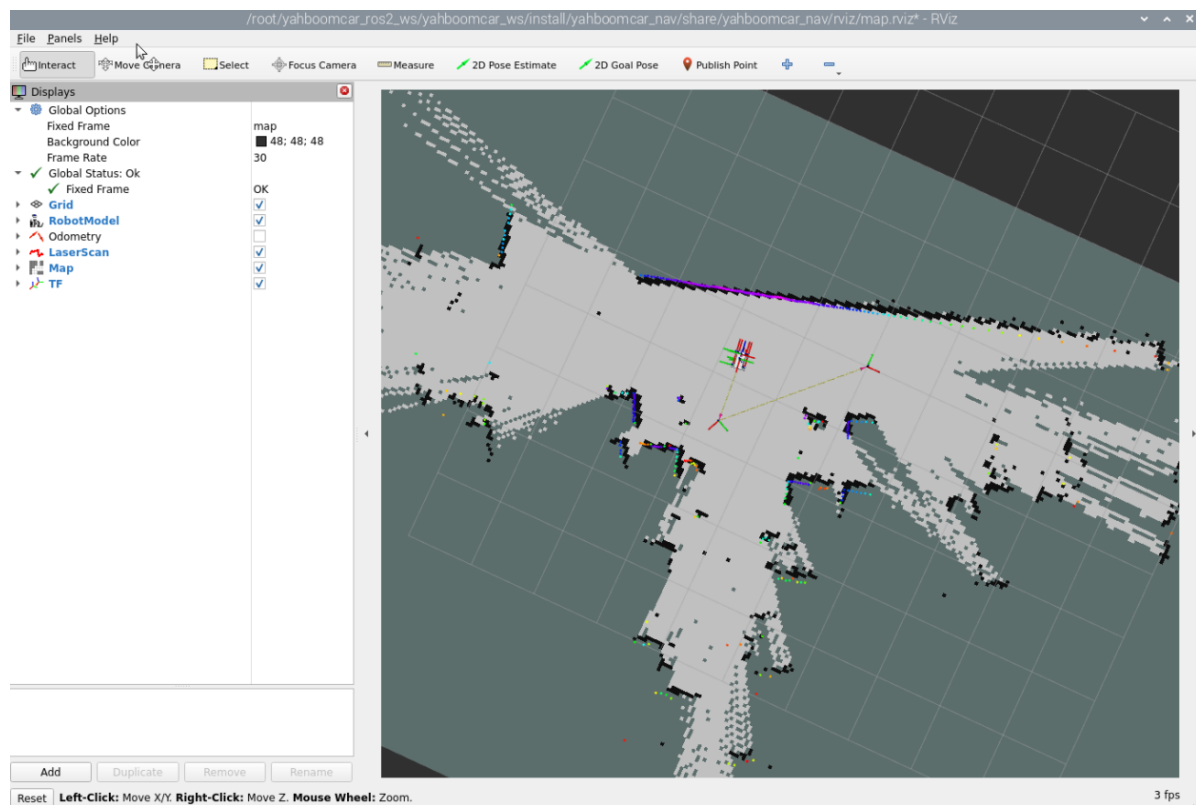
Start Mapping

```
ros2 launch yahboomcar_nav map_slam_toolbox_launch.py
```

```
root@raspberrypi:~# ros2 launch yahboomcar_nav map_slam_toolbox_launch.py  
[INFO] [launch]: All log files can be found below /root/.ros/log/2025-08-12-19-55-40-423895-raspberrypi-149912  
[INFO] [launch]: Default logging verbosity is set to INFO  
----- robot_type = A1, rplidar_type = tmini, camera_type = nuwa -----  
-----robot_type = A1-----  
[INFO] [ydlidar_ros2_driver_node-9]: process started with pid [149968]  
[INFO] [joint_state_publisher-1]: process started with pid [149944]  
[INFO] [robot_state_publisher-2]: process started with pid [149946]  
[INFO] [Ackman_driver_A1-3]: process started with pid [149948]  
[INFO] [base_node_A1-4]: process started with pid [149950]  
[INFO] [imu_filter_madgwick_node-5]: process started with pid [149952]  
[INFO] [ekf_node-6]: process started with pid [149954]  
[INFO] [yahboom_joy_A1-7]: process started with pid [149957]  
[INFO] [joy_node-8]: process started with pid [149966]  
[INFO] [static_transform_publisher-10]: process started with pid [149971]  
[INFO] [static_transform_publisher-11]: process started with pid [149973]  
[INFO] [static_transform_publisher-12]: process started with pid [149983]  
[INFO] [sync_slam_toolbox_node-13]: process started with pid [149991]  
[robot_state_publisher-2] [INFO] [1754999741.752895637] [robot_state_publisher]: got segment base_footprint  
[robot_state_publisher-2] [INFO] [1754999741.753098005] [robot_state_publisher]: got segment base_link  
[robot_state_publisher-2] [INFO] [1754999741.753123579] [robot_state_publisher]: got segment camera_link  
[robot_state_publisher-2] [INFO] [1754999741.753133875] [robot_state_publisher]: got segment imu_link  
[robot_state_publisher-2] [INFO] [1754999741.753143283] [robot_state_publisher]: got segment laser  
[robot_state_publisher-2] [INFO] [1754999741.753151912] [robot_state_publisher]: got segment left_front_wheel_joint  
[robot_state_publisher-2] [INFO] [1754999741.753160875] [robot_state_publisher]: got segment left_rear_wheel_hinge  
[robot_state_publisher-2] [INFO] [1754999741.753169005] [robot_state_publisher]: got segment left_steering_hinge_joint  
[robot_state_publisher-2] [INFO] [1754999741.753179634] [robot_state_publisher]: got segment right_front_wheel_joint  
[robot_state_publisher-2] [INFO] [1754999741.753189023] [robot_state_publisher]: got segment right_rear_wheel_hinge  
[robot_state_publisher-2] [INFO] [1754999741.753196949] [robot_state_publisher]: got segment right_steering_hinge_joint  
[imu_filter_madgwick_node-5] [INFO] [1754999741.764256084] [imu_filter_madgwick]: Starting ImuFilter  
[imu_filter_madgwick_node-5] [INFO] [1754999741.770803318] [imu_filter_madgwick]: Using dt computed from message headers  
[imu_filter_madgwick_node-5] [INFO] [1754999741.770911520] [imu_filter_madgwick]: The gravity vector is kept in the IMU message.  
[imu_filter_madgwick_node-5] [INFO] [1754999741.771305998] [imu_filter_madgwick]: Imu filter gain set to 0.100000  
[imu_filter_madgwick_node-5] [INFO] [1754999741.771360627] [imu_filter_madgwick]: Gyro drift bias set to 0.000000  
[imu_filter_madgwick_node-5] [INFO] [1754999741.771379108] [imu_filter_madgwick]: Magnetometer bias values: 0.000000 0.000000 0.000000
```

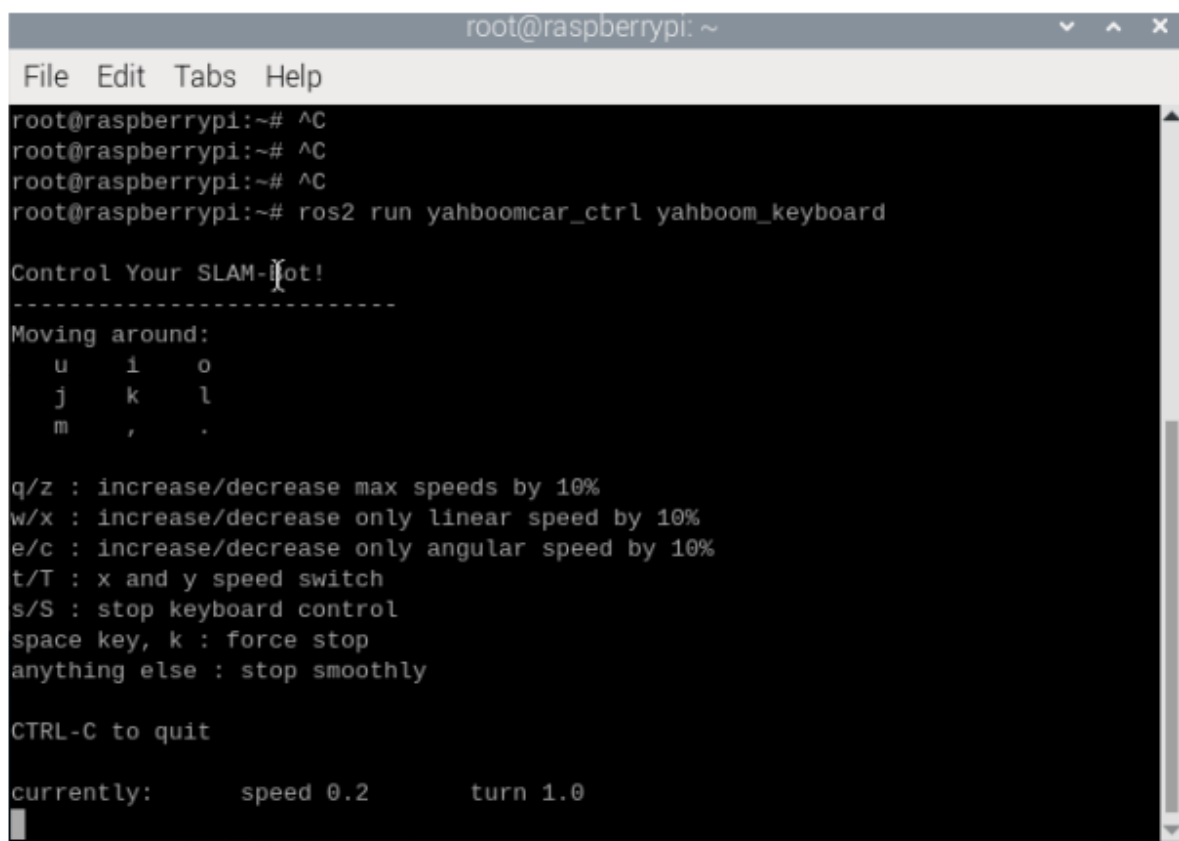
Enter the command to start rviz visualization mapping.

```
ros2 launch yahboomcar_nav display_map_launch.py
```

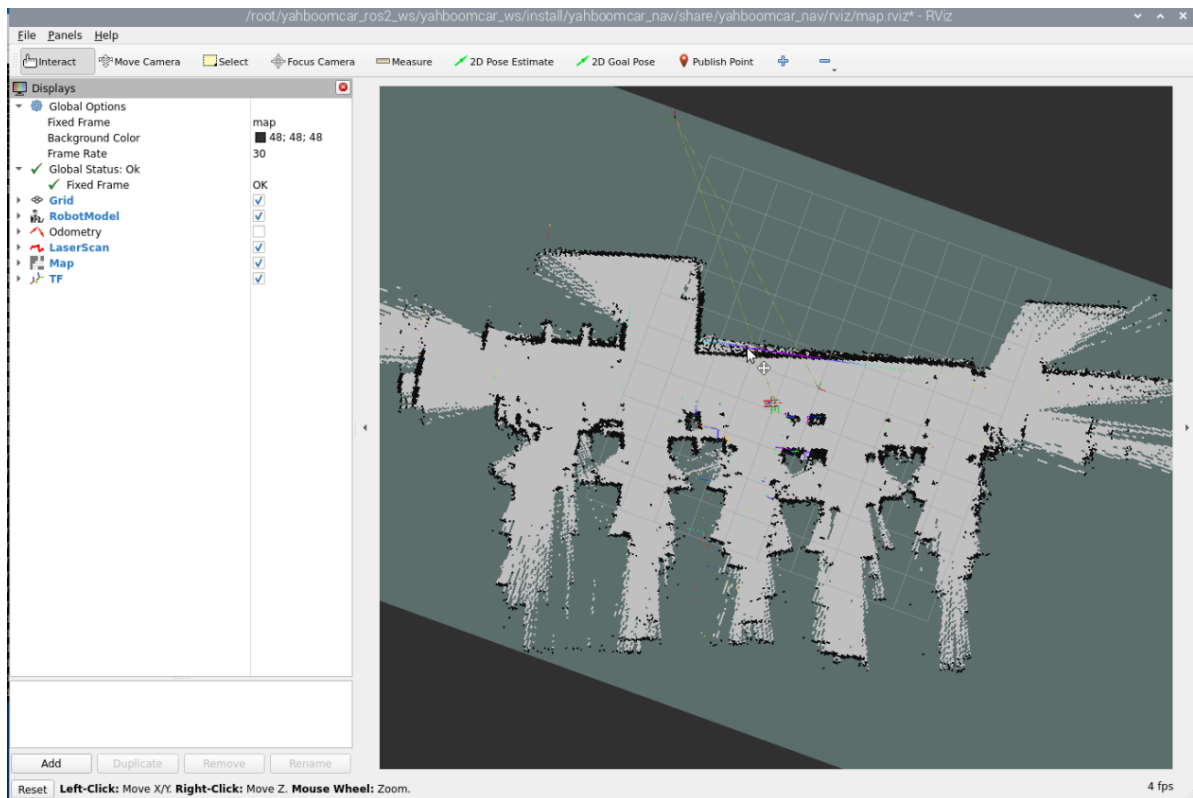


The program has controller control enabled by default. If you're using a controller, you can now connect it directly to the receiver for control. To control it using the keyboard, enter the following in the terminal:

```
#keyboard
ros2 run yahboomcar_ctrl yahboom_keyboard
```



Then control the car and slowly navigate the area to be mapped.



After mapping is complete, enter the following command to save the map. In the terminal, enter:

```
ros2 launch yahboomcar_nav save_map_launch.py
```

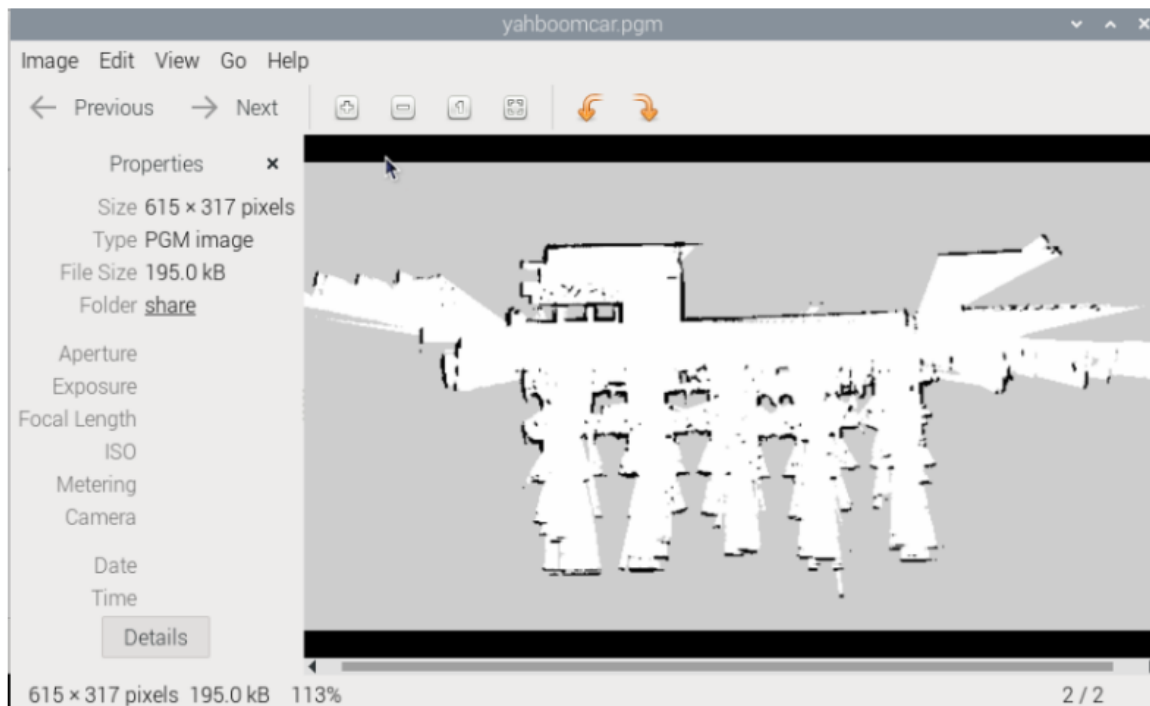
root@raspberrypi: /
代码语言

```
File Edit Tabs Help
[INFO] [map_saver_cli-1]: process started with pid [85580]
[map_saver_cli-1] [INFO] [1754993160.071993975] [map_saver]:
[map_saver_cli-1]      map_saver lifecycle node launched.
[map_saver_cli-1]      Waiting on external lifecycle transitions to activate
[map_saver_cli-1]      See https://design.ros2.org/articles/node_lifecycle.html for more information.
[map_saver_cli-1] [INFO] [1754993160.072179828] [map_saver]: Creating
[map_saver_cli-1] [INFO] [1754993160.072646034] [map_saver]: Configuring
[map_saver_cli-1] [INFO] [1754993160.076916391] [map_saver]: Saving map from 'map' topic to '/root/yahboomcar_ros2_ws/yahboomcar_ws/src/yahboomcar_nav/maps/yahboomcar.pgm' file
[map_saver_cli-1] [WARN] [1754993160.077106800] [map_saver]: Free threshold unspecified. Setting it to default value: 0.250000
[map_saver_cli-1] [WARN] [1754993160.077128078] [map_saver]: Occupied threshold unspecified. Setting it to default value: 0.650000
[map_saver_cli-1] [WARN] [1754993160.101062396] [map_io]: Image format unspecified. Setting it to: pgm
[map_saver_cli-1] [INFO] [1754993160.101142767] [map_io]: Received a 317 X 615 map @ 0.05 m/pix
[map_saver_cli-1] [INFO] [1754993160.241443101] [map_io]: Writing map occupancy data to /root/yahboomcar_ros2_ws/yahboomcar_ws/src/yahboomcar_nav/maps/yahboomcar.pgm
[map_saver_cli-1] [INFO] [1754993160.244221227] [map_io]: Writing map metadata to /root/yahboomcar_ros2_ws/yahboomcar_ws/src/yahboomcar_nav/maps/yahboomcar.yaml
[map_saver_cli-1] [INFO] [1754993160.251699343] [map_io]: Map saved
[map_saver_cli-1] [INFO] [1754993160.251775899] [map_saver]: Map saved successfully
[map_saver_cli-1] [INFO] [1754993160.253474927] [map_saver]:
[INFO] [map_saver_cli-1]: process has finished cleanly [pid 85580]
root@raspberrypi:/#
```

A map named yahboomcar will be saved. This map is saved in:

```
~/yahboomcar_ros2_ws/yahboomcar_ws/src/yahboomcar_nav/maps/yahboomcar.yaml
```

Two files will be generated, one named yahboomcar.pgm. The map is as follows (for Orin boards, you can directly double-click the map. For Raspberry Pi boards, you need to copy the file to /root/share in Docker). (This is the shared folder, then view it on the host machine.)



yahboom_map.yaml, take a look at the contents of the yaml file.

```
image: yahboomcar.pgm
mode: trinary
resolution: 0.05
origin: [-9.02, -15.5, 0]
negate: 0
occupied_thresh: 0.65
free_thresh: 0.25
```

- image: The image representing the map, i.e., yahboomcar.pgm
- mode: This property can be one of trinary, scale, or raw, depending on the selected mode. Trinary is the default mode.
- resolution: The resolution of the map, in meters/pixels
- origin: The 2D coordinate system at the bottom left corner of the map. Pose (x, y, yaw), where yaw is counterclockwise rotation (yaw=0 means no rotation). Currently, many parts of the system ignore the yaw value.
- negate: Whether to invert the meaning of white/black and free/occupied (this does not affect the interpretation of thresholds).
- occupied_thresh: Pixels with an occupied probability greater than this threshold are considered fully occupied.
- free_thresh: Pixels with an occupied probability less than this threshold are considered completely free.

5. View the Node Communication Graph

In the terminal, enter:

```
ros2 run rqt_graph rqt_graph
```


/slam_toolbox/scan_visualization: sensor_msgs/msg/LaserScan
/slam_toolbox/update: visualization_msgs/msg/InteractiveMarkerUpdate
/tf: tf2_msgs/msg/TFMessage

Service Servers:

/slam_toolbox/clear_changes: slam_toolbox/srv/Clear
/slam_toolbox/describe_parameters: rcl_interfaces/srv/DescribeParameters
/slam_toolbox/deserialize_map: slam_toolbox/srv/DeserializePoseGraph
/slam_toolbox/dynamic_map: nav_msgs/srv/GetMap
/slam_toolbox/get_interactive_markers:

visualization_msgs/srv/GetInteractiveMarkers

/slam_toolbox/get_parameter_types: rcl_interfaces/srv/GetParameterTypes
/slam_toolbox/get_parameters: rcl_interfaces/srv/GetParameters
/slam_toolbox/list_parameters: rcl_interfaces/srv/ListParameters
/slam_toolbox/manual_loop_closure: slam_toolbox/srv/LoopClosure
/slam_toolbox/pause_new_measurements: slam_toolbox/srv/Pause
/slam_toolbox/save_map: slam_toolbox/srv/SaveMap
/slam_toolbox/serialize_map: slam_toolbox/srv/SerializePoseGraph
/slam_toolbox/set_parameters: rcl_interfaces/srv/SetParameters
/slam_toolbox/set_parameters_atomically:

rcl_interfaces/srv/SetParametersAtomically

/slam_toolbox/toggle_interactive_mode: slam_toolbox/srv/ToggleInteractive

Service Clients:

Action Servers:

Action Clients: