SLAM Steps (ROS2 Nav2 Course - Section 3)

Those commands are the ones you will run in this section on SLAM. Use this PDF to easily access them while doing the exercises.

Some of the commands are specific to the Turtlebot3 robot, which we use as an example. Later on in the course (Section 7), you will also get the general commands to run for any robots.

Steps

When you see some text in red, replace it with the correct value.

1. Start your robot stack

$ ros2 launch turtlebot3_gazebo turtlebot3_world.launch.py

2. Start SLAM

$ ros2 launch turtlebot3_cartographer cartographer.launch.py use_sim_time:=True

3. Make the robot move to generate the map

$ ros2 run turtlebot3_teleop teleop_keyboard

4. Save the map

$ ros2 run nav2_map_server map_saver_cli -f ~/my_map