

Navigation Steps (ROS2 Nav2 Course - Section 4)

Those commands are the ones you will run in this section on Navigation. 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

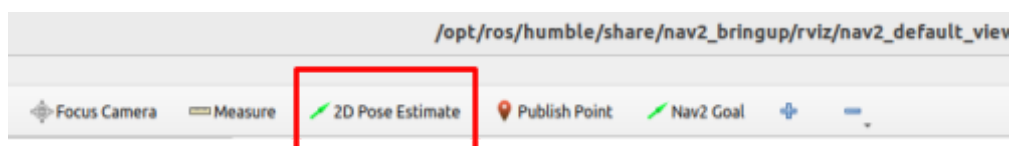
```
$ ros2 launch turtlebot3_gazebo turtlebot3_ world.launch.py
```

2. Start Navigation 2

```
$ ros2 launch turtlebot3_navigation2 navigation2.launch.py use_sim_time:=True  
map:=path/to/world_map.yaml
```

3. Set 2D Pose Estimate

Click on RViz



4. Send a Navigation2 Goal

Click on RViz

