Criss Task Final 2

1. Hector Slam and 2D Mapping

For this step i downloaded hector slam package, then modified the mapping\_default.launch file to get ‘laser link’ and also modified tutorial.launch file in hector\_slam\_launch directory , where I changed the usr\_sim\_time to False as I had to put live data connection to gazebo, if i had to use bag file then this value should have been false. After this I run

Mobile\_manipulator.launch and tutorial.launch files along with remote control , so that to steer through the world

1. Stereo Camera and 3D Mapping

Firstly I have added a stereo camera code into the mobile\_manipulator.urdf file after then this would stream data to rtab\_map so as to make a 3D map. And for 2D occupancy map can be obtained similarly.