Husky Tutorials

To work with the Husky robot in the next tutorials we will first have to install some packages. These are 3 packages you need.

```
$ sudo apt-get install ros-melodic-husky-navigation
$ sudo apt-get install ros-melodic-husky-gazebo
$ sudo apt-get install ros-melodic-husky-viz
```

Note that, even if you are working with a different ROS-version than melodic you could still install these packages. In most case you could simply replace melodic by the name if your distro, for example: kinetic.

In your **first terminal** open up the Gazebo world:

```
$ roslaunch husky_gazebo husky_playpen.launch
```

It will look similar to:
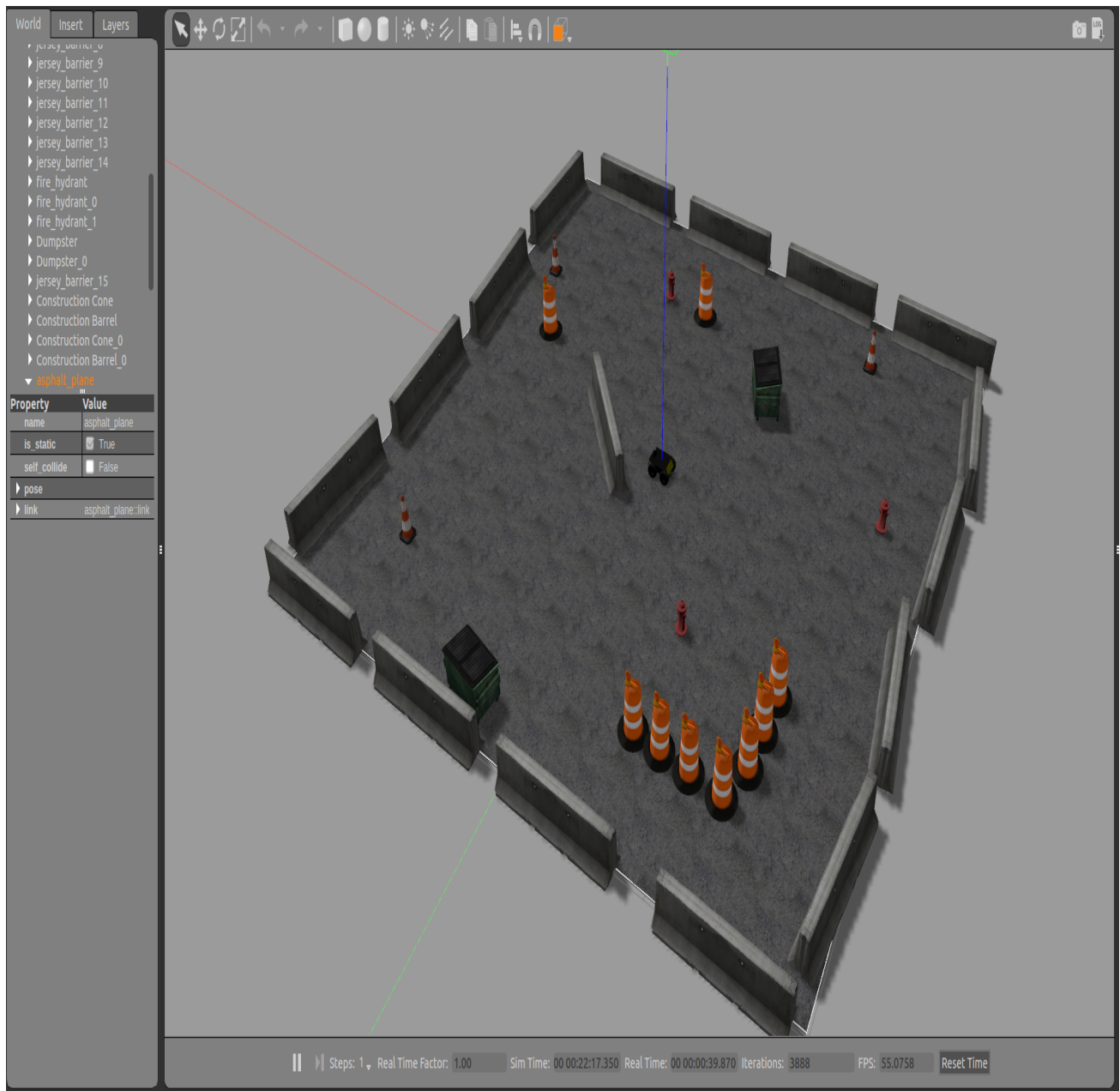
In the **second terminal** open up Rviz with the Clear-path configuration:

```
$ roslaunch husky_viz view_robot.launch
```

In your **third terminal** start off gmapping.

```
$ roslaunch husky_navigation gmapping_demo.launch
```

Now, use *2D Nav Goal* tool in the top toolbar to select a movement goal in RViz.

To save the generated map, you can run the map_saver utility:

```
$ rosrun map_server map_saver -f <filename>
```