INSTRUCTIONS TO RUN “MEETING_EXAMPLE.M”

1. Add “multi-robot-gspnr-toolbox” and subfolders to Matlab Path;
2. Place the provided catkin package “matlab_execution_tests” in your catkin workspace and build using the command:

   catkin_make

3. Start up the dummy action servers for the Navigate/Mop/Vacuum actions either by:
   - Executing each one individually by running the commands:

     rosrun matlab_execution_tests navigating_server_tb1.py
     rosrun matlab_execution_tests mopping_server_tb1.py
     rosrun matlab_execution_tests vacuuming_server_tb1.py
     rosrun matlab_execution_tests navigating_server_tb2.py
     rosrun matlab_execution_tests mopping_server_tb2.py
     rosrun matlab_execution_tests vacuuming_server_tb1.py

   - Using the launch file (NOT TESTED) by running the following command:

     roslaunch matlab_execution_tests launch_action_servers.launch

4. Change variable “catkin_package_path” to a path of a valid catkin package – this is where the toolbox’s interface action servers will be saved and executed out of;
5. Run “meeting_example.m”;
6. Start a roscore;
7. When prompted, run the python interface scripts. The name of each of these scripts is:

   “matlab_interface_server_<robot_name>.py”

8. By default, as the robots names’ are “tb1” and “tb2”, and you must run the commands:

   “rosrun <catkin_package_name> matlab_interface_server_tb1.py”
   “rosrun <catkin_package_name> matlab_interface_server_tb2.py”