(   )

0.5

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```
ros2 launch originbot_bringup originbot.launch.py
```

- (use_camera:=true   use_lidar:=true imu use_imu:=true)

```
ros2 launch originbot_bringup originbot.launch.py use_camera:=true use_lidar:=true use_imu:=
```

```
ros2 run originbot_linefollower follower
```

SSH

```
ros2 run teleop_twist_keyboard teleop_twist_keyboard
```

```
halt
```

odom

```
ros2 run originbot_demo echo_odom
```

originbot_demo/echo_odom.py

```
ros2 run originbot_demo echo_status
```

originbot_demo/echo_status.py

3s

```
ros2 run originbot_demo control_buzzer
```

: originbot_demo/control_buzzer.py

LED

LED 3s

```
ros2 run originbot_demo control_led
```

originbot_demo/control_led.py

```
ros2 run originbot_demo draw_circle
```

originbot_demo/draw_circle.py