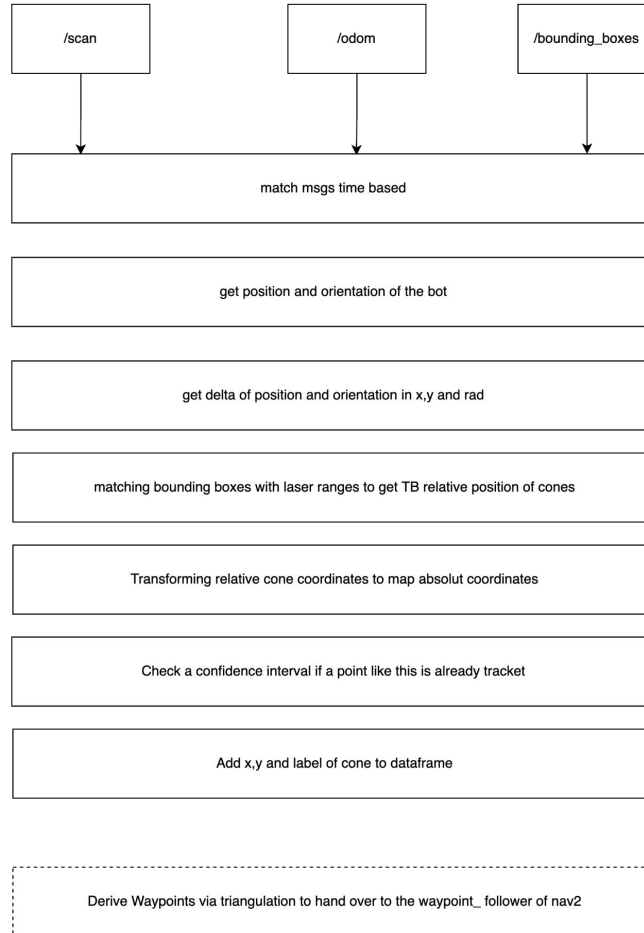
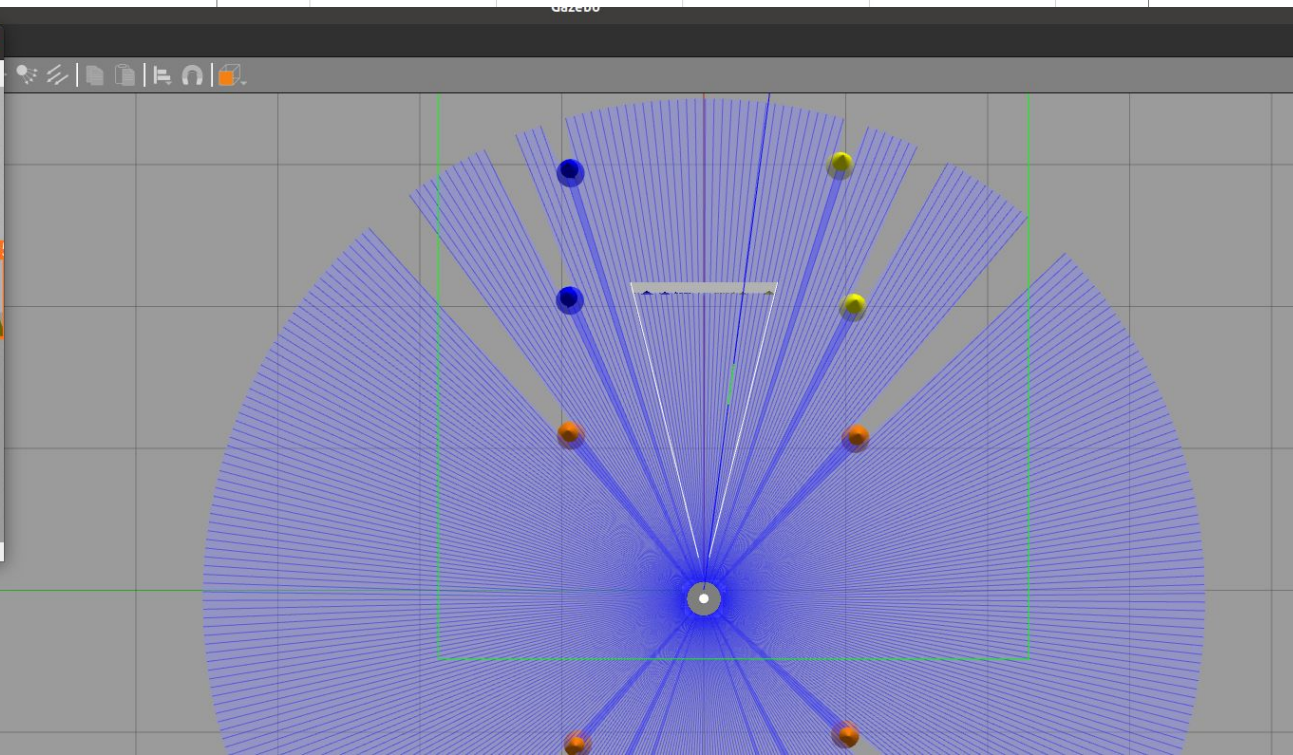
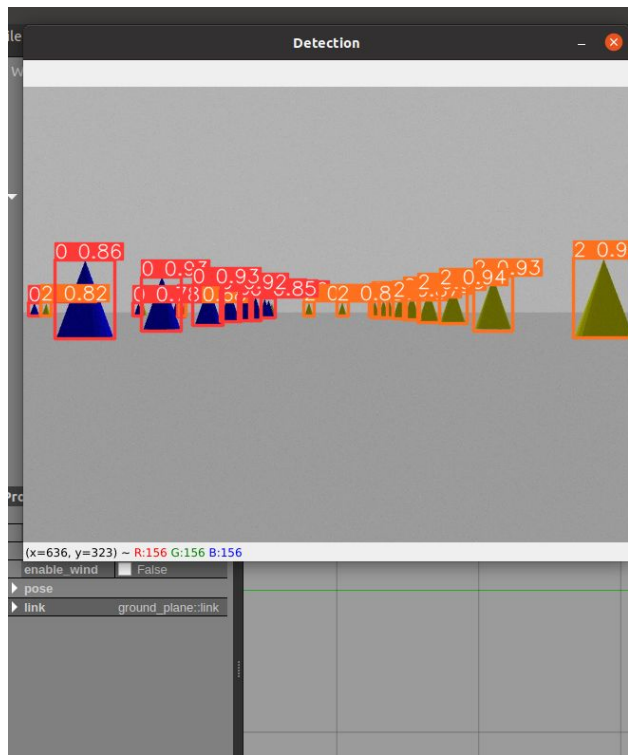
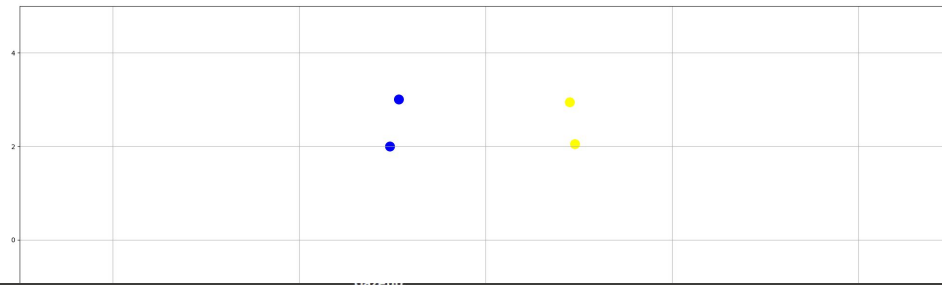


# Assignment 4 - SLAM

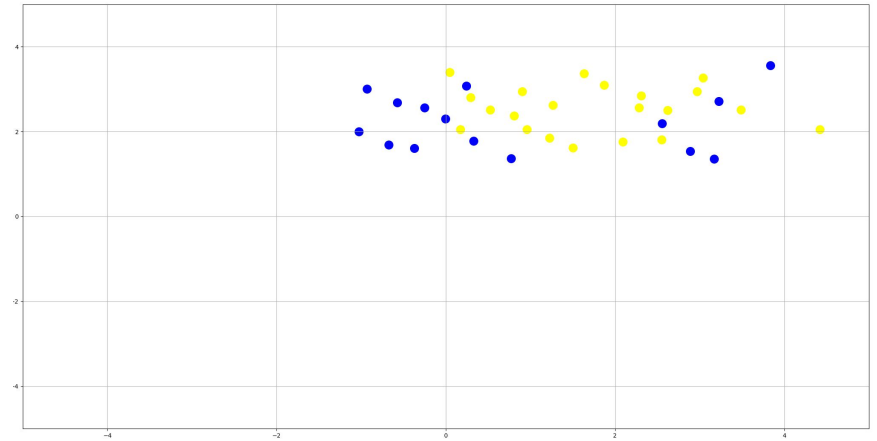
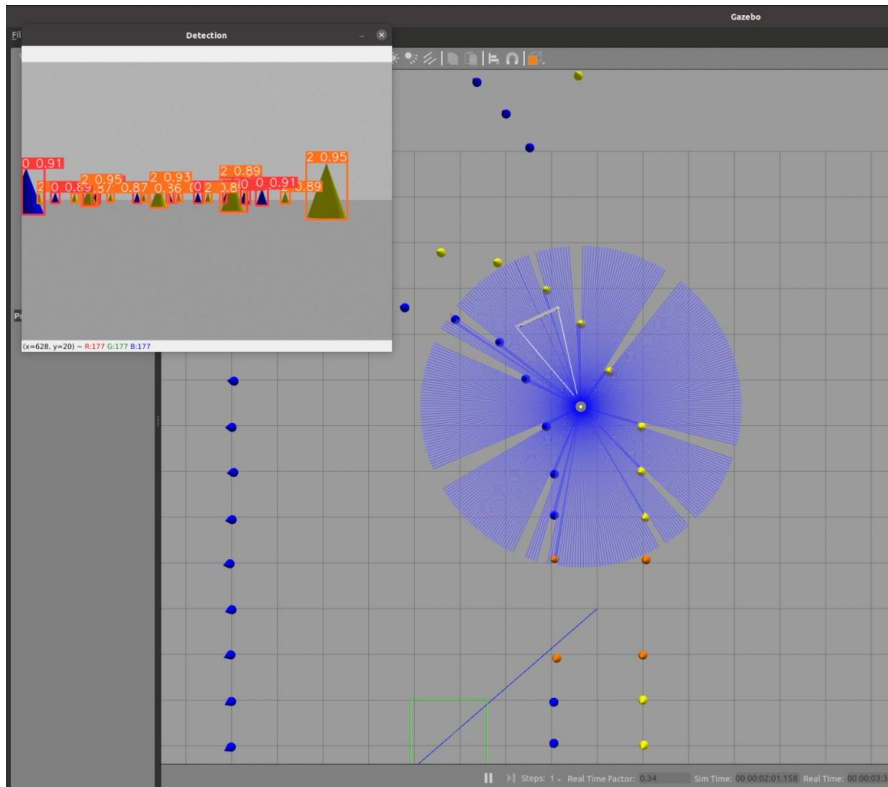
# Our Approach



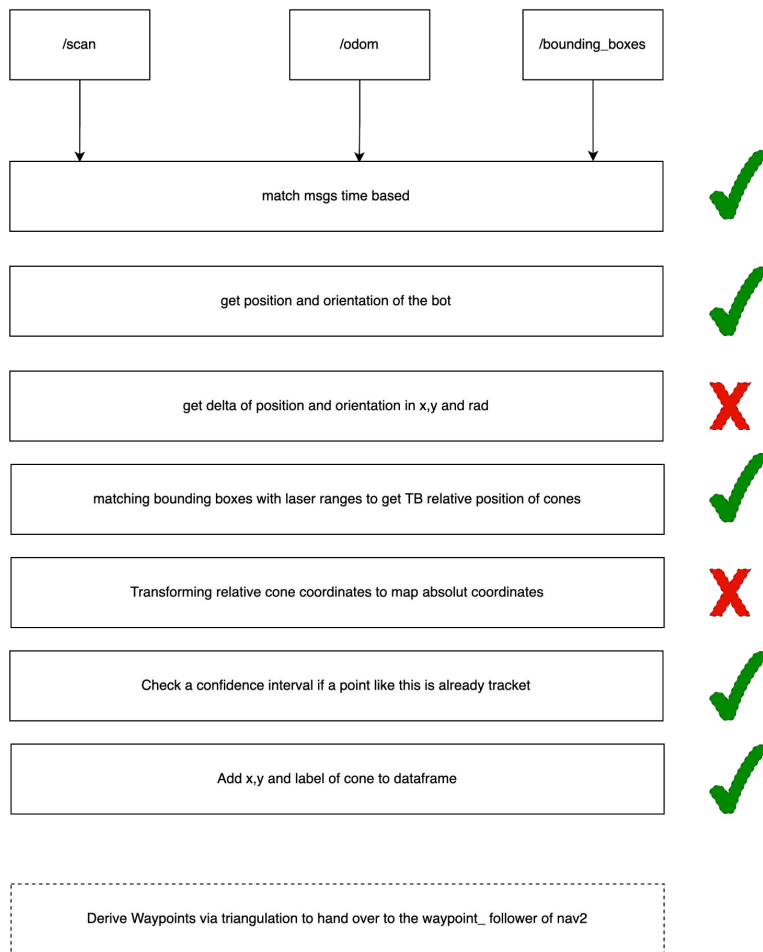
Looks good first



# But then it does not

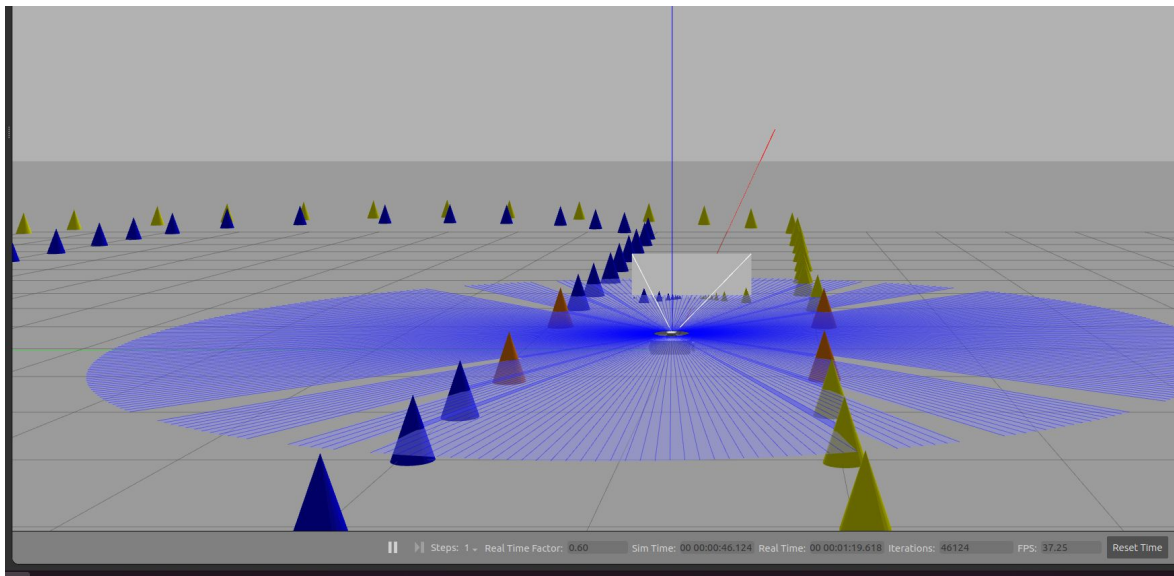


# Current state



# Problems & Delays

- creating the simulation
- making everything run in simulation (extra node for simulated camera)



# Dead Ends

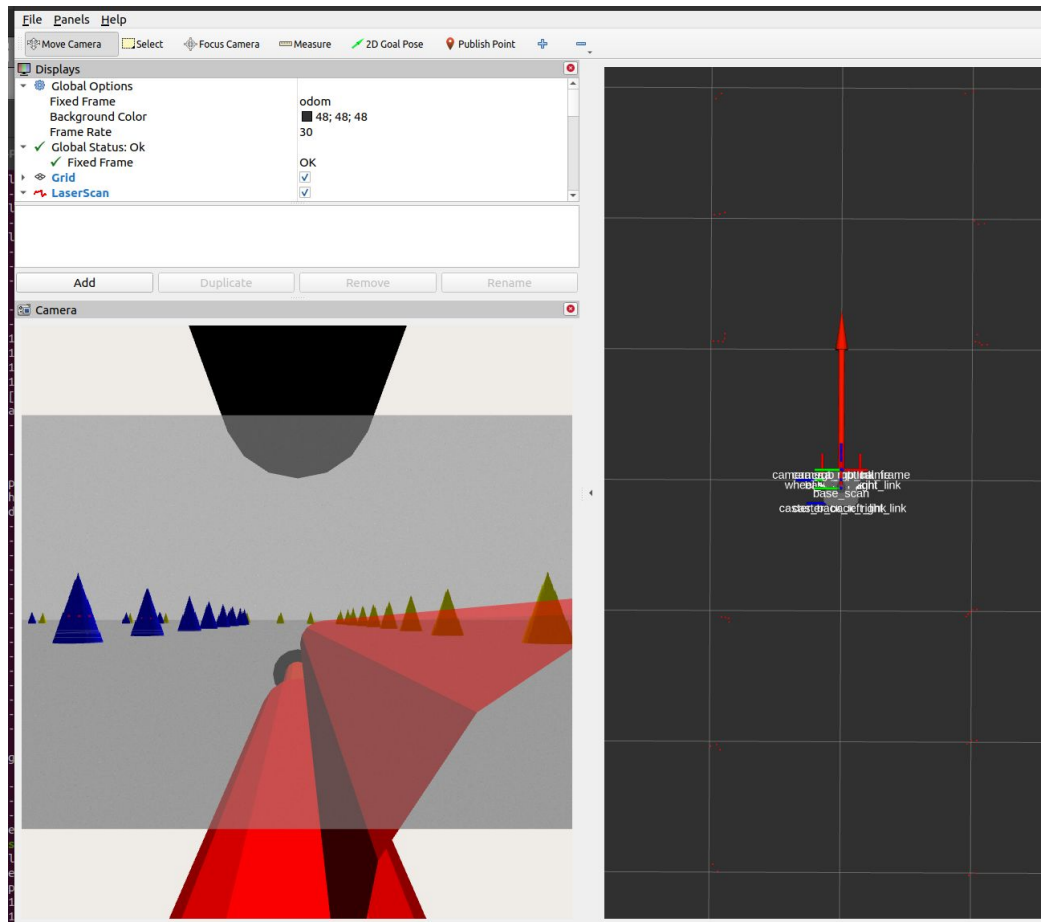
- /scanMatchedPoints
- Slam Toolbox
- Nav2

## API

The following are the services/topics that are exposed for use. See the rviz plugin for an implementation of their use.

### Subscribed topics

/scan	sensor_msgs/LaserScan	the input scan from your laser to utilize
tf	N/A	a valid transform from your configured odom_frame to base_frame



## To dos:

- Fix coordinate transformations
  - Learn about: Quaternion and Euler angles
- Test on real turtlebot

## Challenges

- Very time consuming tasks
- Tasks are not really splittable between multiple team members