**Layer1（第一层）**

* 电梯前面：[ (0.03, -1.2, 0), (0, 0, 1, 1)]
* Room1 → **ReceptionRoom（接待室）**：[ (-5, -1.8, 0), (0, 0, 1, 1)]
* Room2 → **LectureHall（教室）**：[ (3.58, 4.30, 0), (0, 0, 1, 1)]
* Room3 → **AdminOffice（行政办公室）**：[ (9.7, 0.1, 0), (0, 0, 0, 1)]

Layer2文件gazebo和riz启动的初始参数设置，原来的位置建筑和机器人重叠了

<!-- 定义机器人初始位置参数 -->

<arg name="init\_x" default="-3.0"/>

<arg name="init\_y" default="-0.5"/>

<arg name="init\_z" default="0.0"/>

**Layer2（第二层）**

* 电梯位置：[ (-0.7, -0.65, 0), (0, 0, -1, 1)]
* Room1 → **Lab（实验室）**：[ (-3.414, -3.633, 0), (0, 0, -1, 1)]
* Room2 → **Classroom（教室）**：[ (2.315, -3.346, 0), (0, 0, 0, 1)]
* Room3 → **SeminarRoom（研讨室）**：[ (5.888, -1.195, 0), (0, 0, 0, 1)]

**Layer3（第三层）**

* 电梯位置：[ (-0.998, -1.223, 0), (0, 0, 1, 1)]
* Room1 → **ProfessorOffice（教授办公室）**：[ (-7.293, -5.396, 0), (0, 0, -1, 1)]
* Room2 → **Library（图书室）**：[ (-3.267, 3.461, 0), (0, 0, 1, 1)]
* Room3 → **StudyRoom（自习室）**：[ (5.319, 2.264, 0), (0, 0, 0, 1)]