Update the max speed (max\_vel\_x in teb planner)

The initial setting of max\_vel\_x in teb\_local\_planner\_params\_carlike.yaml is 2.0 (i.e. 2 m/s). For me, that is too fast for initial testing. To reduce that I followed these instructions.

* Ctrl-Atl-t
* Start the Docker container
* # cd /root/tractor\_ws/src/lawn\_tractor/lawn\_tractor\_navigation/config
* # vim teb\_local\_planner\_params\_carlike.yaml
* Find the statement below

# Robot

max\_vel\_x: 2.0 {replace with your new value for example .75, 1.0, 1.5}

* + Insert - to insert characters
  + :w{enter} - to write the edits
  + :q{enter} - to quit the editor
* # cd /root/tractor\_ws
* # catkin build && source devel/setup.bash
* Save the Docker image, $ docker ps # to gather container name

| al@al-ThinkPad-W530:~$ docker commit -m "update max speed" busy\_gould rosagriculture/lawn\_tractor  sha256:f9445f311513b1fce067777c12c125efefcbab33a36d38d3b45cbe4e79228d34  al@al-ThinkPad-W530:~$ |
| --- |

* $ docker commit -m ‘update speed’ busy\_gould rosagriculture/lawn\_tractor

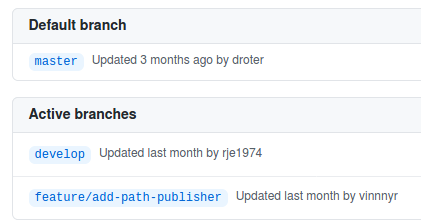
To get a local version:

$git pull origin branch\_name

* $ git clone https://github.com/ros-agriculture/ros\_lawn\_tractor.git

<https://github.com/ros-agriculture/lawn_tractor.git>

git pull {repo} {remotebranchname}:{localbranchname}



Problem statement: How to start the develop branch on the physical laptop.

Try it now; Maybe it works.