<launch>

<arg name="no\_static\_map" default="true"/>

<arg name="odom\_frame\_id" default="robot1\_tf/odom"/>

<arg name="base\_frame\_id" default="robot1\_tf/base\_link"/>

<arg name="global\_frame\_id" default="map" />

<arg name="odom\_topic" default="/robot1/odom" />

<arg name="laser\_topic" default="/robot1/scan"/>

<node pkg="move\_base" type="move\_base" respawn="false" name="move\_base" output="screen">

<rosparam file="$(find p3dx\_navigation)/config/costmap\_common\_params.yaml" command="load" ns="global\_costmap" />

<rosparam file="$(find p3dx\_navigation)/config/costmap\_common\_params.yaml" command="load" ns="local\_costmap" />

<rosparam file="$(find p3dx\_navigation)/config/local\_costmap\_params.yaml" command="load" />

<rosparam file="$(find p3dx\_navigation)/config/global\_costmap\_params.yaml" command="load" />

<rosparam file="$(find p3dx\_navigation)/config/move\_base\_params.yaml" command="load" />

<!-- NOTE: Use move\_base\_global.launch for globally qualified map topic -->

<!-- START: Use with estop -->

<!-- <remap from="cmd\_vel" to="cmd\_vel\_estop"/>-->

<!-- END: Use with estop -->

<!--rosparam file="$(arg custom\_param\_file)" command="load"/-->

<param name="global\_costmap/global\_frame" value="$(arg global\_frame\_id)"/>

<param name="global\_costmap/robot\_base\_frame" value="$(arg base\_frame\_id)"/>

<param name="local\_costmap/global\_frame" value="$(arg odom\_frame\_id)"/>

<param name="local\_costmap/robot\_base\_frame" value="$(arg base\_frame\_id)"/>

<remap from="cmd\_vel" to="/robot1/cmd\_vel" />

<remap from="odom" to="$(arg odom\_topic)" />

<remap from="scan" to="$(arg laser\_topic)" />

<remap from="map" to="/map" />

<remap from="/move\_base/TebLocalPlannerROS/global\_plan" to="/robot1/move\_base/TebLocalPlannerROS/global\_plan" />

<remap from="/move\_base/TebLocalPlannerROS/local\_plan" to="/robot1/move\_base/TebLocalPlannerROS/local\_plan" />

<remap from="/move\_base/TebLocalPlannerROS/teb\_markers" to="/robot1/move\_base/TebLocalPlannerROS/teb\_markers"/>

<remap from="/move\_base/TebLocalPlannerROS/teb\_markers\_array" to="/robot1/move\_base/TebLocalPlannerROS/teb\_markers\_array"/>

<remap from="/move\_base/TebLocalPlannerROS/teb\_poses" to="/robot1/move\_base/TebLocalPlannerROS/teb\_poses"/>

<remap from="/move\_base/global\_costmap/costmap" to="/robot1/move\_base/global\_costmap/costmap"/>

<remap from="/move\_base/global\_costmap/costmap\_updates" to="/robot1/move\_base/global\_costmap/costmap\_updates"/>

<remap from="/move\_base/local\_costmap/costmap" to="/robot1/move\_base/local\_costmap/costmap"/>

<remap from="/move\_base/local\_costmap/costmap\_updates" to="/robot1/move\_base/local\_costmap/costmap\_updates"/>

<remap from="/move\_base/local\_costmap/footprint" to="/robot1/move\_base/local\_costmap/footprint"/>

<remap from="/move\_base/GlobalPlanner/parameter\_descriptions" to="/robot1/move\_base/GlobalPlanner/parameter\_descriptions"/>

<remap from="/move\_base/GlobalPlanner/parameter\_updates" to="/robot1/move\_base/GlobalPlanner/parameter\_updates"/>

<remap from="/move\_base/GlobalPlanner/plan" to="/robot1/move\_base/GlobalPlanner/plan"/>

<remap from="/move\_base/GlobalPlanner/potential" to="/robot1/move\_base/GlobalPlanner/potential"/>

<remap from="/move\_base/TebLocalPlannerROS/obstacles" to="/robot1/move\_base/TebLocalPlannerROS/obstacles"/>

<remap from="/move\_base/TebLocalPlannerROS/parameter\_descriptions" to="/robot1/move\_base/TebLocalPlannerROS/parameter\_descriptions"/>

<remap from="/move\_base/TebLocalPlannerROS/parameter\_updates" to="/robot1/move\_base/TebLocalPlannerROS/parameter\_updates"/>

<remap from="/move\_base/cancel" to="/robot1/move\_base/cancel"/>

<remap from="/move\_base/current\_goal" to="/robot1/move\_base/current\_goal"/>

<remap from="/move\_base/feedback" to="/robot1/move\_base/feedback"/>

<remap from="/move\_base/global\_costmap/footprint" to="/robot1/move\_base/global\_costmap/footprint"/>

<remap from="/move\_base/global\_costmap/inflation\_layer/parameter\_descriptions" to="/robot1/move\_base/global\_costmap/inflation\_layer/parameter\_descriptions"/>

<remap from="/move\_base/global\_costmap/inflation\_layer/parameter\_updates" to="/robot1/move\_base/global\_costmap/inflation\_layer/parameter\_updates"/>

<remap from="/move\_base/global\_costmap/obstacle\_layer/clearing\_endpoints" to="/robot1/move\_base/global\_costmap/obstacle\_layer/clearing\_endpoints"/>

<remap from="/move\_base/global\_costmap/obstacle\_layer/parameter\_descriptions" to="/robot1/move\_base/global\_costmap/obstacle\_layer/parameter\_descriptions"/>

<remap from="/move\_base/global\_costmap/obstacle\_layer/parameter\_updates" to="/robot1/move\_base/global\_costmap/obstacle\_layer/parameter\_updates"/>

<remap from="/move\_base/global\_costmap/parameter\_descriptions" to="/robot1/move\_base/parameter\_descriptions"/>

<remap from="/move\_base/global\_costmap/parameter\_updates" to="/robot1/move\_base/global\_costmap/parameter\_updates"/>

<remap from="/move\_base/global\_costmap/static\_layer/parameter\_descriptions" to="/robot1/move\_base/global\_costmap/static\_layer/parameter\_descriptions"/>

<remap from="/move\_base/global\_costmap/static\_layer/parameter\_updates" to="/robot1/move\_base/global\_costmap/static\_layer/parameter\_updates"/>

<remap from="/move\_base/goal" to="/robot1/move\_base/goal"/>

<remap from="/move\_base/local\_costmap/obstacle\_layer/clearing\_endpoints" to="/robot1/move\_base/local\_costmap/obstacle\_layer/clearing\_endpoints"/>

<remap from="/move\_base/local\_costmap/obstacle\_layer/parameter\_descriptions" to="/robot1/move\_base/local\_costmap/obstacle\_layer/parameter\_descriptions"/>

<remap from="/move\_base/local\_costmap/obstacle\_layer/parameter\_updates" to="/robot1/move\_base/local\_costmap/obstacle\_layer/parameter\_updates"/>

<remap from="/move\_base/local\_costmap/parameter\_descriptions" to="/robot1/move\_base/local\_costmap/parameter\_descriptions"/>

<remap from="/move\_base/local\_costmap/parameter\_updates" to="/robot1/move\_base/local\_costmap/parameter\_updates"/>

<remap from="/move\_base/local\_costmap/static\_layer/parameter\_descriptions" to="/robot1/move\_base/local\_costmap/static\_layer/parameter\_descriptions"/>

<remap from="/move\_base/local\_costmap/static\_layer/parameter\_updates" to="/robot1/move\_base/local\_costmap/static\_layer/parameter\_updates"/>

<remap from="/move\_base/parameter\_descriptions" to="/robot1/move\_base/parameter\_descriptions"/>

<remap from="/move\_base/parameter\_updates" to="/robot1/move\_base/parameter\_updates"/>

<remap from="/move\_base/result" to="/robot1/move\_base/result"/>

<remap from="/move\_base/status" to="/robot1/move\_base/status"/>

<remap from="/move\_base\_simple/goal" to="/robot1/move\_base\_simple/goal"/>

<remap from="/move\_base/cancel" to="/robot1/move\_base/cancel" />

<remap from="/move\_base/feedback" to="/robot1/move\_base/feedback"/>

<remap from="/move\_base/goal" to="/robot1/move\_base/goal" />

<remap from="/move\_base/result" to="/robot1/move\_base/result"/>

<remap from="/move\_base/status" to="/robot1/move\_base/status"/>

<remap from="/move\_base/NavfnROS/plan" to="/robot1/move\_base/NavfnROS/plan"/>

<remap from="/move\_base/TrajectoryPlannerROS/cost\_cloud" to="/robot1/move\_base/TrajectoryPlannerROS/cost\_cloud"/>

<remap from="/move\_base/TrajectoryPlannerROS/global\_plan" to="/robot1/move\_base/TrajectoryPlannerROS/global\_plan"/>

<remap from="/move\_base/TrajectoryPlannerROS/local\_plan" to="/robot1/move\_base/TrajectoryPlannerROS/local\_plan"/>

<remap from="/move\_base/TrajectoryPlannerROS/parameter\_descriptions" to="/robot1/move\_base/TrajectoryPlannerROS/parameter\_descriptions"/>

<remap from="/move\_base/TrajectoryPlannerROS/parameter\_updates" to="/robot1/move\_base/TrajectoryPlannerROS/parameter\_updates"/>

<remap from="/move\_base/local\_costmap/inflation\_layer/parameter\_descriptions" to="/robot1/move\_base/local\_costmap/inflation\_layer/parameter\_descriptions"/>

<remap from="/move\_base/local\_costmap/inflation\_layer/parameter\_updates" to="/robot1/move\_base/local\_costmap/inflation\_layer/parameter\_updates"/>

<remap from="/move\_base/DWAPlannerROS/cost\_cloud" to="/robot1/move\_base/DWAPlannerROS/cost\_cloud"/>

<remap from="/move\_base/DWAPlannerROS/global\_plan" to="/robot1/move\_base/DWAPlannerROS/global\_plan"/>

<remap from="/move\_base/DWAPlannerROS/local\_plan" to="/robot1/move\_base/DWAPlannerROS/local\_plan"/>

<remap from="/move\_base/DWAPlannerROS/parameter\_descriptions" to="/robot1/move\_base/DWAPlannerROS/parameter\_descriptions"/>

<remap from="/move\_base/DWAPlannerROS/parameter\_updates" to="/robot1/move\_base/DWAPlannerROS/parameter\_updates"/>

<remap from="/move\_base/DWAPlannerROS/trajectory\_cloud" to="/robot1/move\_base/DWAPlannerROS/trajectory\_cloud"/>

<remap from="/move\_base/global\_costmap/obstacle\_layer/voxel\_grid" to="/robot1/move\_base/global\_costmap/obstacle\_layer/voxel\_grid"/>

<remap from="/move\_base/local\_costmap/obstacle\_layer/voxel\_grid" to="/robot1/move\_base/local\_costmap/obstacle\_layer/voxel\_grid"/>

</node>

</launch>