Rosdep Debugging (Version 1)

Overview

Ros is a working space for robot model training.

Usually it can be divided into two parts: Node and Topic.

Install Ros in Linux system and setup all environment before you proceed this part.

```
cd Desktop/lanelet_ws/
catkin build
```

- Locate ros workspace and build rosdep

```
rosdep install --from-paths src --ignore-src -r -y
catkin build
```

Basic Steps

- Export the Lanelet2 map from Autoware.
- Run the ros

```
roscore
```

- Load map file

```
rosrun map_file lanelet2_map_loader /home/erian/Downloads/mapname
```

```
rosrun map_file lanelet2_map_visualizer
```

- Check the info of map loader and visualizer.

```
rostopic list
rosnode info /lanelet_map_loader
```

```
rosnode info /lanelet_map_visualizer
```

- Check the list of ros topic
- Open rviz application to visualize the map.

```
rviz
```

- If rviz is able to run the map successfully, ignore following steps.

```
rosrun lanelet2_validation lanelet2_validate /home/erian/Downloads/mapname
```

```
rosrun lanelet2_extension autoware_lanelet2_validation _map_file:=/home/erian/Downloads/mapname
```

- Try to fix all errors and rerun the map in rviz

```
rviz
```