镭神C16建图文档

1.建图

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| 1.启动多线激光雷达  cd /home/rob/lslidar\_ros\_v4/  source ./devel/setup.bash  roslaunch lslidar\_driver lslidar\_c16.launch |
| 2.打开bringup  cd /home/rob/lingao\_3D\_16lines/lingaonav\_ws/  source ./devel/setup.bash  roslaunch lingao\_bringup bringup.launch |
| 3.打开移动控制节点  cd /home/rob/lingao\_3D\_16lines/lingaonav\_ws/  source ./devel/setup.bash  roslaunch lingao\_bringup lingao\_teleop\_keyboard.launch |
| 4.录制点云数据,控制小车移动整个建图空间后结束录制  rosbag record /lslidar\_point\_cloud -o /home/rob/mapping/test/laser3lab.bag |
| 5.打开建图节点  cd /home/rob/lingao\_3D\_16lines/slam\_ws/  source ./devel/setup.bash  roslaunch launch/hdl\_graph\_slam\_lingao.launch |
| 6.播放bag包bag\_name需要与上面录制的bag路径保持一致  rosbag play --clock /home/rob/mapping/test/laser3lab.bag |
| 7.保存的.pcd点云图和.bt导航地图  cd /home/rob/lingao\_3D\_16lines/slam\_ws/  source ./devel/setup.bash  roslaunch launch/save\_map.launch pcd\_name:=pcd\_laser3lab bt\_name:=bt\_laser3lab  通过pcl\_viewer pcd\_test2.pcd可以查看创建的三维点云图 |

2.定位导航

cd /home/rob/lingao\_3D\_16lines/lingaonav\_ws/

source ./devel/setup.bash

roslaunch car\_2dnav lingao\_2dnav.launch path:=/home/rob/mapping/test/bt\_laser3lab.bt

启动导航节点后在rviz中给定初始位姿即可