Moving the Robot

Estimated time to completion: **30 seconds**

5.5 Gazebo ROS2 Control Plugin

Using the **ros2_control framework** to move joints of a simulated robot is more complex than native Gazebo plugins, mainly due to the longer learning curve required. However, it has benefits, including an easier transition when moving to the real robot. ROS2_control also implements its own functionality to broadcast the joint states for the robot model's movable joints, but that is much more than we could cover here.

The remainder of this unit will guide you through the basic steps to move a joint using **ros2_control** in simulation. In particular, you will implement it to actuate two joints to:

- Move a laser up and down
- Rotate the laser visual model by velocity around its Z-axis.

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