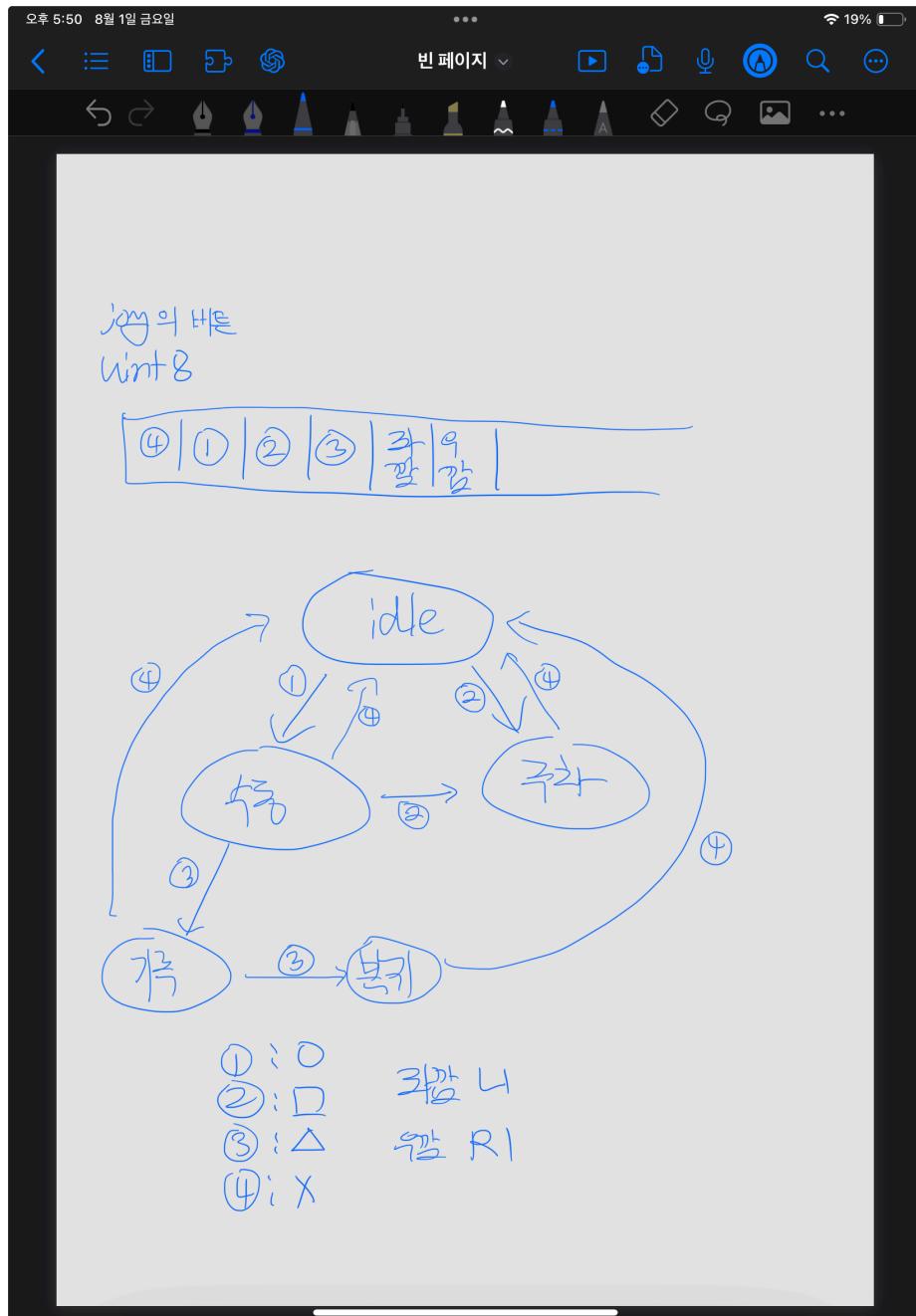# RP4 Status Management

- https://github.com/hiwad-aziz/ros2_odometry_estimation
  - 위치 추정 알고리즘 - 2wheel differential drive model
  - 입력
    - 양쪽 바퀴 rpm(속도)
      - /right_wheel_rpm (std_msgs/Int64): RPM of right wheel
      - /left_wheel_rpm (std_msgs/Int64): RPM of left wheel

- 출력
  - /odom ; 현재 위치 (x,y,theta)
- ⌗ GitHub - Arcanain/pure_pursuit_planner: pure_pursuit_planner
  - 경로 추종 알고리즘
    - 입력
      - /odom
      - /tgt_traj
    - 출력
      - geometry_msgs::msg::Twist cmd_vel
        - 선속도와 각속도

https://github.com/whaleegg/autonomous-skid-steer-rpi