## 1) GENERATE A GAZEBO WORLD

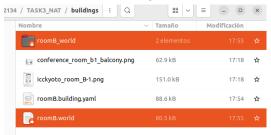
```
Unset
# Se hace dentro del root
```

cd buildings/

ros2 run rmf\_building\_map\_tools building\_map\_generator gazebo
roomB.building.yaml roomB.world ./roomB\_world

```
root@170cff8361c1:/rmf_demos_ws# cd buildings/
root@170cff8361c1:/rmf_demos_ws/buildings# ros2 run rmf_building_map_tools building_map_generator gaz
ebo roomB.building.yam1 roomB.world ./roomB_world
generating roomB.world from roomB.building.yaml
building name: roomB
coordinate system: reference_image
parsing level L1
parsing level L1
parsing level L2
calculating levels relative to L1
level L1 scale: 0.03400760034914868
calculating level L2 offset and scale...
2 common fiducials:
Transform.set_from_fiducials()
2 fiducial pairs:
    (736.43, -1268.1) -> (916.08, -1421.3) right_column
    (569.03, -1268.8) -> (689.9, -1420.1) left_column
    calc dist right_column <=> left_column
Bearings:
[(-3.136855617404778, 3.1361280821516564)]
```

## Tiene que crearte lo siguiente:



## 2) VIEW THE GAZEBO WORLD

```
Unset
```

ros2 run rmf\_building\_map\_tools building\_map\_model\_downloader
roomB.building.yaml -e ./models

export GZ\_SIM\_RESOURCE\_PATH=`pwd`/roomB\_world:`pwd`/models

// Usamos este export para cuando tengamos ya el robot, sino solo
usamos el primer export
export

GZ\_SIM\_RESOURCE\_PATH=`pwd`/roomB\_world:`pwd`/models:/rmf\_demos\_ws/ins
tall/rmf\_demos\_assets/share/rmf\_demos\_assets/models

gz sim -r -v 3 roomB.world