

## 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 gazebo roomB.building.yaml roomB.world ./roomB_world
generating roomB.world from roomB.building.yaml
building name: roomB
coordinate system: reference_image
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:

2134 / TASK3_NAT / buildings			
Nombre	Tamaño	Modificación	
roomB_world	2 elementos	17:55	☆
conference_room_b1_balcony.png	62.9 kB	17:18	☆
icckyoto_room_B-1.png	151.0 kB	17:18	☆
roomB.building.yaml	88.6 kB	17:54	☆
roomB.world	80.5 kB	17:55	☆

## 2) VIEW THE GAZEBO WORLD

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```
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/install/rmf_demos_assets/share/rmf_demos_assets/models
```

```
gz sim -r -v 3 roomB.world
```