Note: you need to return to the directory where src is located and compile with catkin\_make command

The equipment we use is AutoLab pro1 robot and velodyne 16 line lidar

ROS version is ros-melodic

The system is ubuntu18.04

autolabor\_ keyboard\_ control and autolabor\_ pro1\_ Driver is the control program of autolabor pro1 robot

The scripts folder under the mapper\_sub folder stores the edge cloud communication program in kubeedge

Below the maps folder is the map of our experimental site

Below the velodyne folder is the official program of velodyne lidar

Under the navigation melody devel folder are the robot navigation, obstacle avoidance, positioning and other programs

The robot simulation environment and program are stored under the simulation folder

Startup files stored under the launch/robot\_navigation/launch folder

/catkin\_workspace/src/launch/robot\_navigation/launch/1.launch start actual robot experiment /catkin\_workspace/src/maps/out10.yaml is a map of the actual environment

/catkin\_workspace/src/launch/robot\_navigation/launch/sim\_robot\_navigation.launch start the simulation experiment /catkin\_workspace/src/simulation/map1/1.yaml is a map of the simulation environment