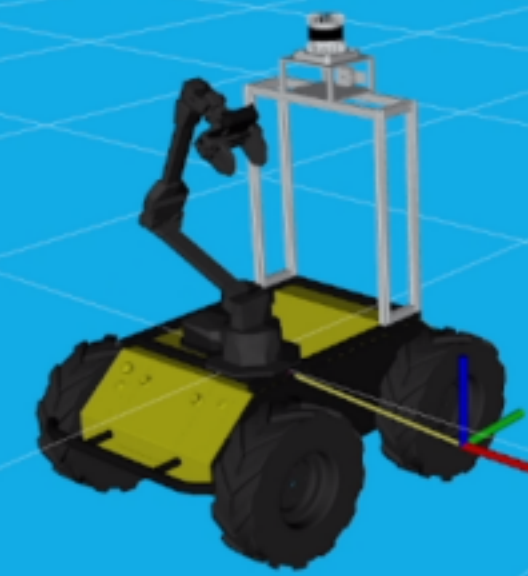
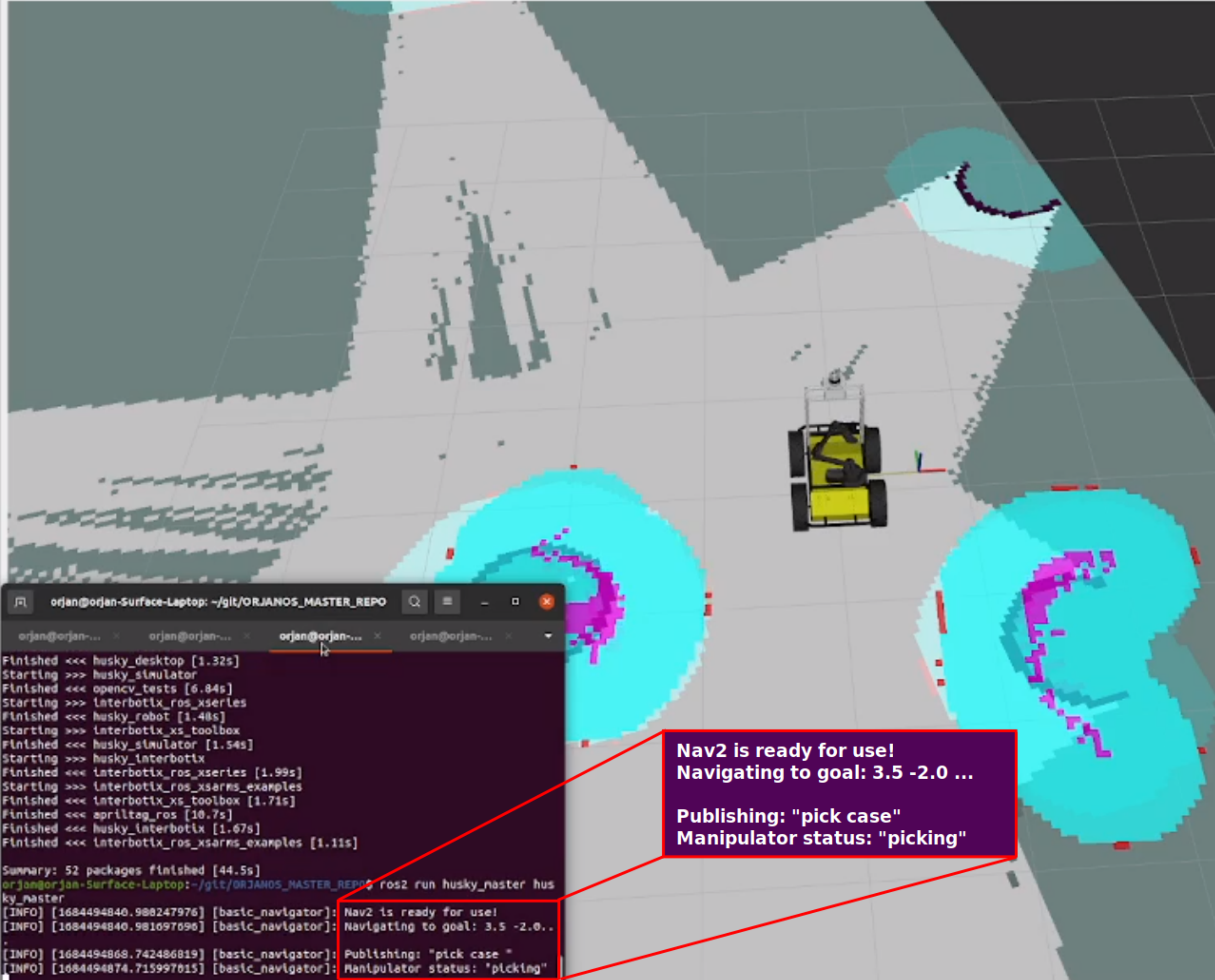


Digital Twin



Gazebo Simulation



```
orjan@orjan-Surface-Laptop: ~/git/ORJANOS_MASTER_REPO
orjan@orjan-... x orjan@orjan-... x orjan@orjan-... x orjan@orjan-... x
Finished <<< husky_desktop [1.32s]
Starting >>> husky_simulator
Finished <<< opencv_tests [6.84s]
Starting >>> interbotix_ros_xseries
Finished <<< husky_robot [1.48s]
Starting >>> interbotix_xs_toolbox
Finished <<< husky_simulator [1.54s]
Starting >>> husky_interbotix
Finished <<< interbotix_ros_xseries [1.99s]
Starting >>> interbotix_ros_xsarms_examples
Finished <<< interbotix_xs_toolbox [1.71s]
Finished <<< apriltag_ros [10.7s]
Finished <<< husky_interbotix [1.67s]
Finished <<< interbotix_ros_xsarms_examples [1.11s]

Summary: 52 packages finished [44.5s]
orjan@orjan-Surface-Laptop:~/git/ORJANOS_MASTER_REPO$ ros2 run husky_master husky_master
[INFO] [1684494840.908247976] [basic_navigator]: Nav2 is ready for use!
[INFO] [1684494840.981697090] [basic_navigator]: Navigating to goal: 3.5 -2.0...
[INFO] [1684494868.742486819] [basic_navigator]: Publishing: "pick case"
[INFO] [1684494874.715997015] [basic_navigator]: Manipulator status: "picking"
```

Nav2 is ready for use!
Navigating to goal: 3.5 -2.0 ...

Publishing: "pick case"
Manipulator status: "picking"