

Some Tips

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- How to improve?
- Tune the navigation stack parameters. Some parameters like (planner parameter ,robot parameter, controller frequency , planning frequency , frequency by which ar_tracker package detecting the markers , inflation distance, radius of pointcloud , base_footprint radius) will have great impact on the planner performance.
- change the local planner (might use TEB ,APF) .
- how to change the planner ? see link = [ros__org](https://www.ros.org) and check TEB course at skills.move
- Handle edge cases , what if you don't see any any markers / or desired marker in camera ? solution : might need to send camera control command to pan/tilt the camera to view marker , might need to rotate the drone to see the marker .
- Test your codes on the real drone .