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`roslaunch hw2 mapping.launch` # to run the assignment mapping nodes

The grid probabilities are stored in a 2D matrix which is then displayed as an OpenCV image after proper axes transformations. Each cell is 5cm in width and there are around 320*320 pixels on the complete map

On completely mapping the environment, the saved map can be found in the folder ./map. The final map resembles the environment under the assumption that the localization has no uncertainty.

Commonly used Brehensam's line algorithm is written to find the pixel coordinates along the laser lines and mark them as empty spaces.