Week 5 - Exercises (28/2)

No lecture today. You will continue to work on the exercises.

**Resetting the position of the robot w/o restarting through roslaunch, from matlab:**

resetpublisher = rospublisher("/reset")

resetMsg = rosmessage(resetpublisher)

send(resetpublisher,resetMsg)

**Be mindful of whether the angles need to be in radians or degrees when given to the functions you use (e.g. for plotting).**