

locobot (via SSH)

remote laptop

Step 1: nav.

Step 2: rviz.

Step 3: controller

or teleop_twist_keyboard.

Let robot to
go somewhere
do circles to
generate one map.



Warning:
name matching.



data_path := "~/ros/rtabmap_XXX.db"



map-name := XXXXX

mapping

Step 4: Localization

Step 2: rviz

Step 5: Visualization
(with rosbaglaunch)

Step 6: Save points
using keyboard.

save
points.

Step 4: Localization

Step 2: rviz

Step 5: Visualization
(with rosbaglaunch)

Step 7: waypoints move

go through
these points