

1. Setup the SMB simulation

see Lecture1/catkin_ws/src/README.md

2. Launch the simulation with roslaunch and inspect the created nodes and their topics

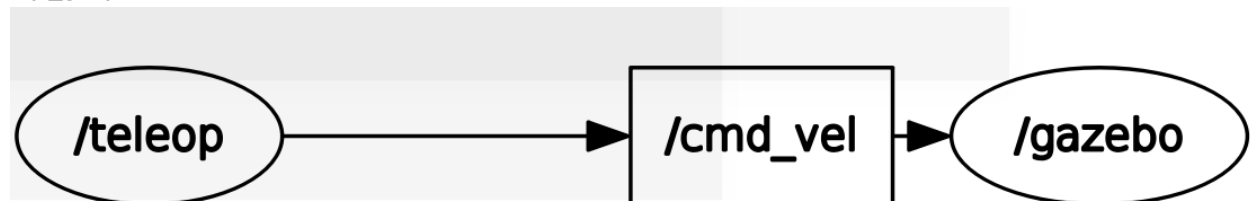
roscd

rostopic list

rostopic echo [TOPIC]

rostopic hz [TOPIC]

rqt_graph



3. Command a desired velocity to the robot from the terminal

rostopic pub /cmd_vel geometry_msgs/Twist

"linear:

x: 0.0

y: 0.0

z: 0.0

angular:

x: 0.0

y: 0.0

z: 1.0"

4. Use teleop_twist_keyboard to control your robot using the keyboard

roslaunch teleop_twist_keyboard teleop_twist_keyboard.py

5. Write a launch file with the following content :

- smb simulation with a different world: Include smb_gazebo.launch file and change the world_file argument to a world from the directory /usr/share/gazebo-9/worlds
see smb_gazebo_robot.launch