LiDAR Instructions:

<https://velodynelidar.com/downloads/>

On this site, go to Manuals and watch the Installation Video (for the Puck) to see how to set up the LiDAR. The package doesn’t come with the flashdrive anymore so you’ll have to install the software from the Velodyne’s website or follow the instructions on the second link to use it on Linux.

[velodyne/Tutorials/Getting Started with the Velodyne VLP16 - ROS Wiki](http://wiki.ros.org/velodyne/Tutorials/Getting%20Started%20with%20the%20Velodyne%20VLP16)

This site will explain how to set up a Velodyne LiDAR on a Linux machine using ROS.

# Use Case:

The LiDAR can be used to feed information to the ROS Navigation stack. Go to this link to see how to set it up: <http://wiki.ros.org/navigation>

Go ahead and install GMapping from this Github repo: <https://github.com/ros-perception/slam_gmapping>

You can also use rtab mapping to make a 3D map with the LiDAR’s pointcloud data. First install RTAB-Map from this Github page: <https://github.com/introlab/rtabmap> . Then install the ROS Wrapper: <http://wiki.ros.org/rtabmap_ros>