In order to configure the SLAM node ‘move\_base’ to the environment we first made copies of the configuration files used in cpmr\_ch7. There were 4 configuration files within that project: base\_local\_planner\_params.yaml, costmap\_common\_params.yaml, global\_costmap\_params.yaml, and local\_costmap\_params.yaml. The help of <http://library.isr.ist.utl.pt/docs/roswiki/navigation(2f)Tutorials(2f)RobotSetup.html> and <https://www.youtube.com/watch?v=bXNK8VTQ4zo> was used in verifying what parameters should be changed to configure the node to our environment. For local\_costmap\_params, the width and height fields were changed to 12.0 each, displaying that the map will be a 12m-by-12m area and the resolution in accordance with the generated map files was left at 0.05. For global\_costmap\_params the origin\_x and origin\_y fields were changed to the origin given in the map output.yaml which is -100 for both, again keeping the resolution at 0.05. The other 2 parameter files were left unchanged. Costmap\_common\_params was not changed because the fields obstacle\_range, raytrace\_range, robot\_radius, and inflaction\_radius was sufficient enough going from a 10m2 area to a 12m2 area. Similarly base\_local\_planner\_params was also not changed because the velocity and acceleration fields were reasonable for the environment that we were using.