



Hochschule
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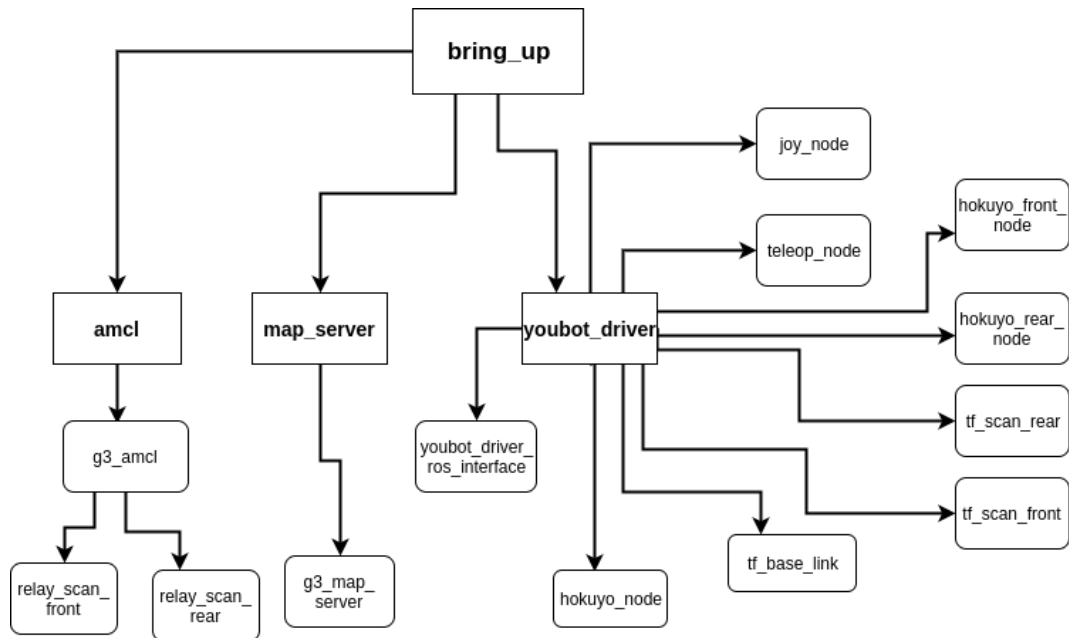
Software Development Project

Basic Navigation Test Analysis

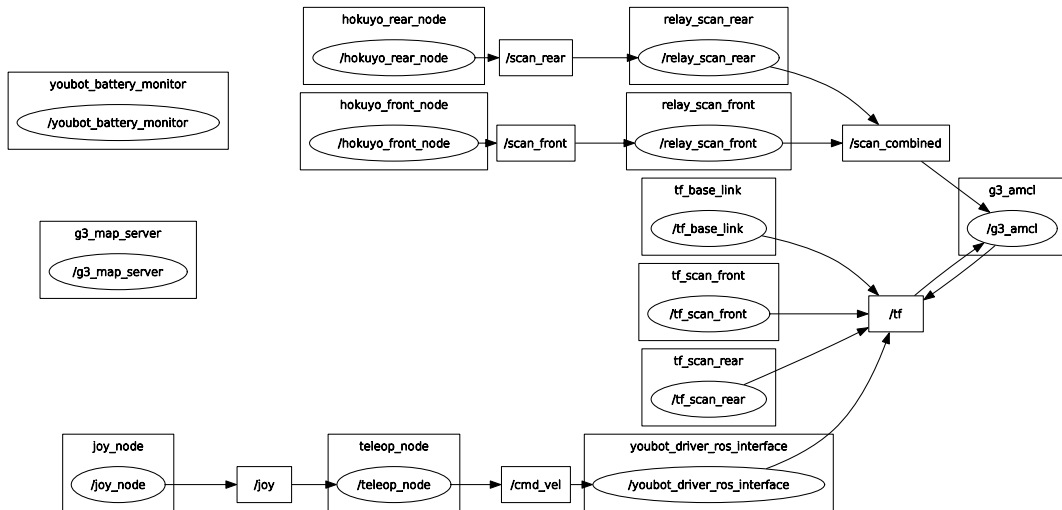
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Launch Files

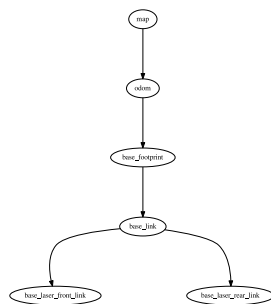


RQT graph



Frames description

- map
 - map is a world fixed frame
 - discrete property make it a poor reference frame for local sensing and acting
- odom
 - pose of robot in the odom frame can drift over time
 - useful as an accurate, short-term local reference
- base_footprint
 - robot position on the ground
 - used for object avoidance
- base_link
- base_laser_front_link
- base_laser_rear_link



Problem

