EECS 476 Mobile Robotics

PS 7

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1. Overview

A linear steering algorithm has been used here to drive a mobot to do something interesting.

1. Main Steps

Start up gazebo, load the mobot model, desired-state publisher, desired-state client, and linear-steering algorithm.

`roslaunch gazebo\_ros empty\_world.launch`

`roslaunch mobot\_urdf mobot.launch`

`rosrun mobot\_pub\_des\_state mobot\_pub\_des\_state`

`rosrun my\_steering\_algorithm\_console my\_steering\_algorithm\_console`

`rosrun lin\_steering lin\_steering\_wrt\_odom`

or

launch file:

'roslaunch my\_lin\_steering\_console my\_lin\_steering\_console.launch'

1. Results

I designed a path for the robot so that it can wander inside the starting pen model and go outside, which can be viewed at

https://youtu.be/a29PjalhPUA