SLAM (cartographer) on Turtlebot2 using ROS2

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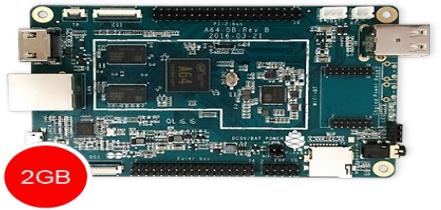
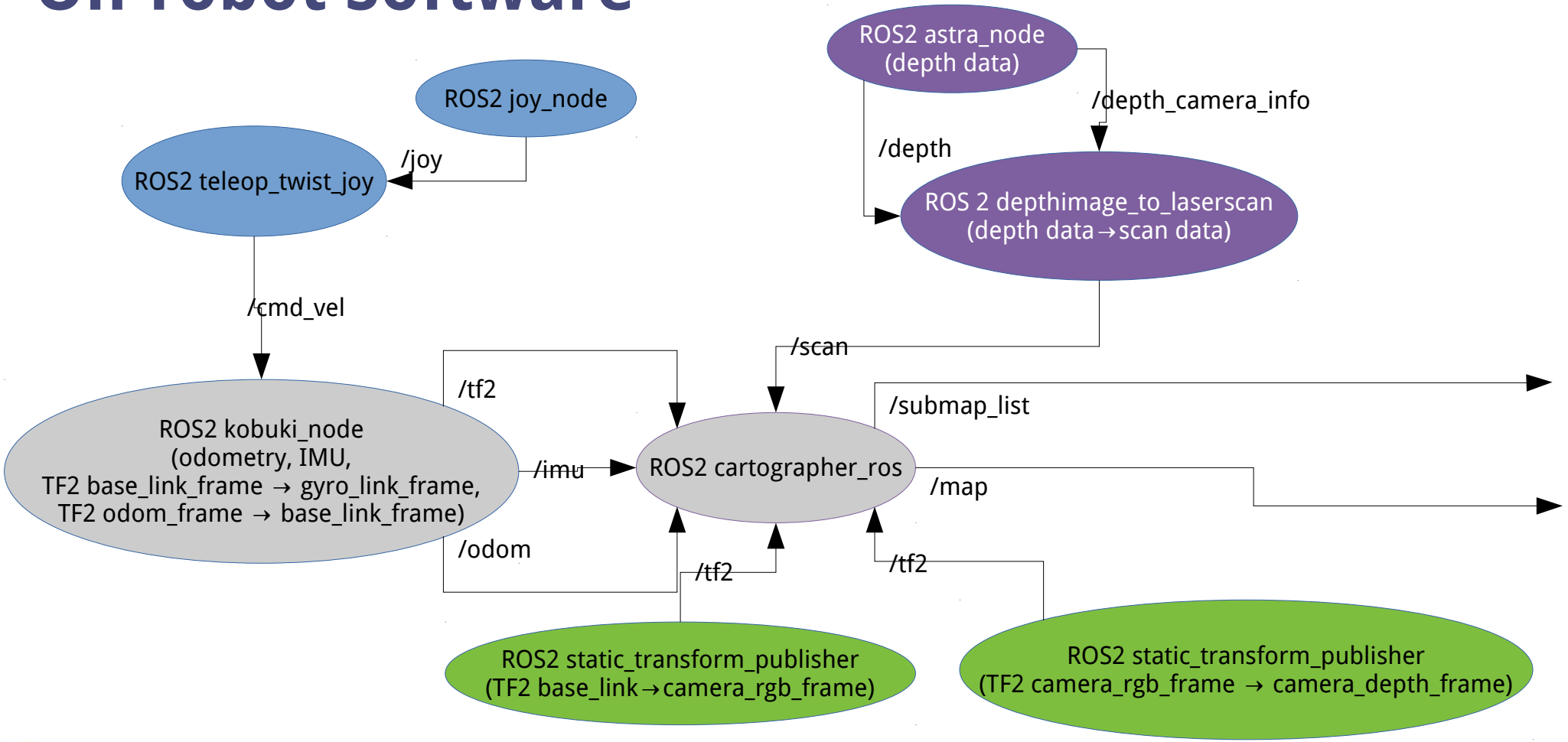
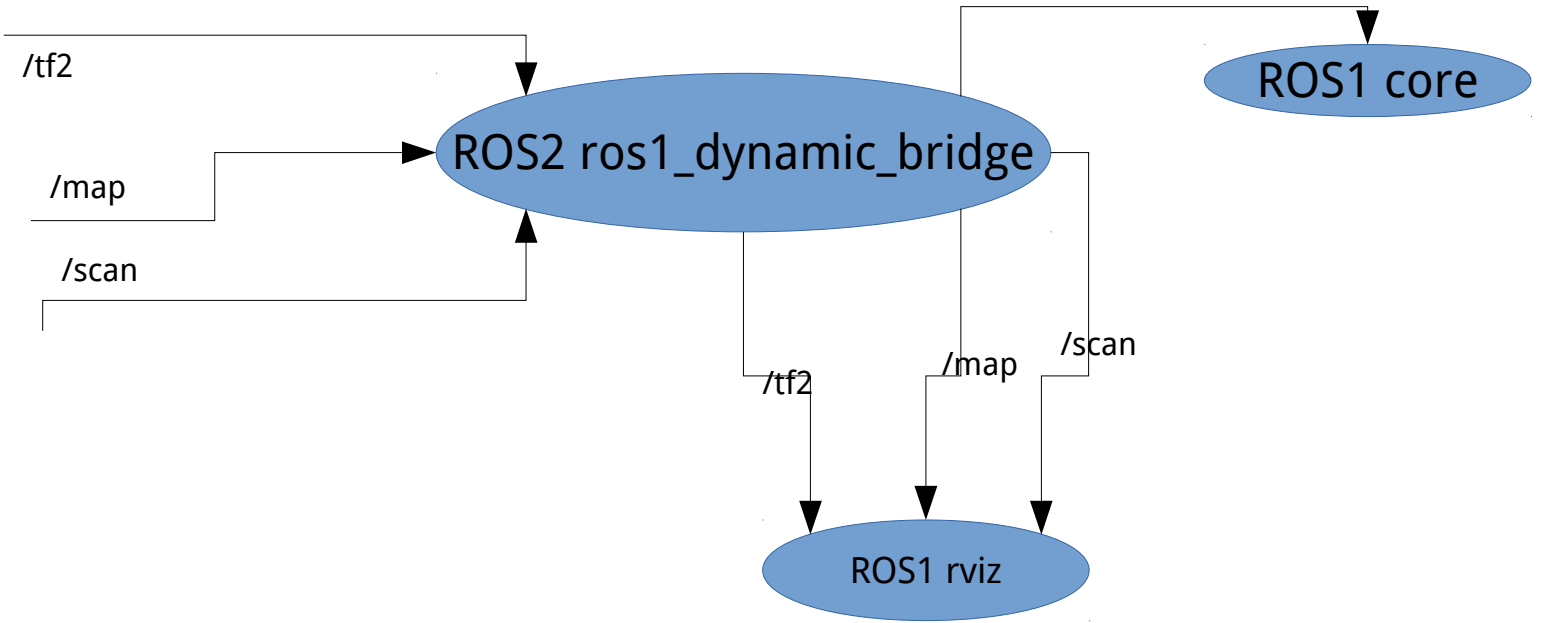
Hardware

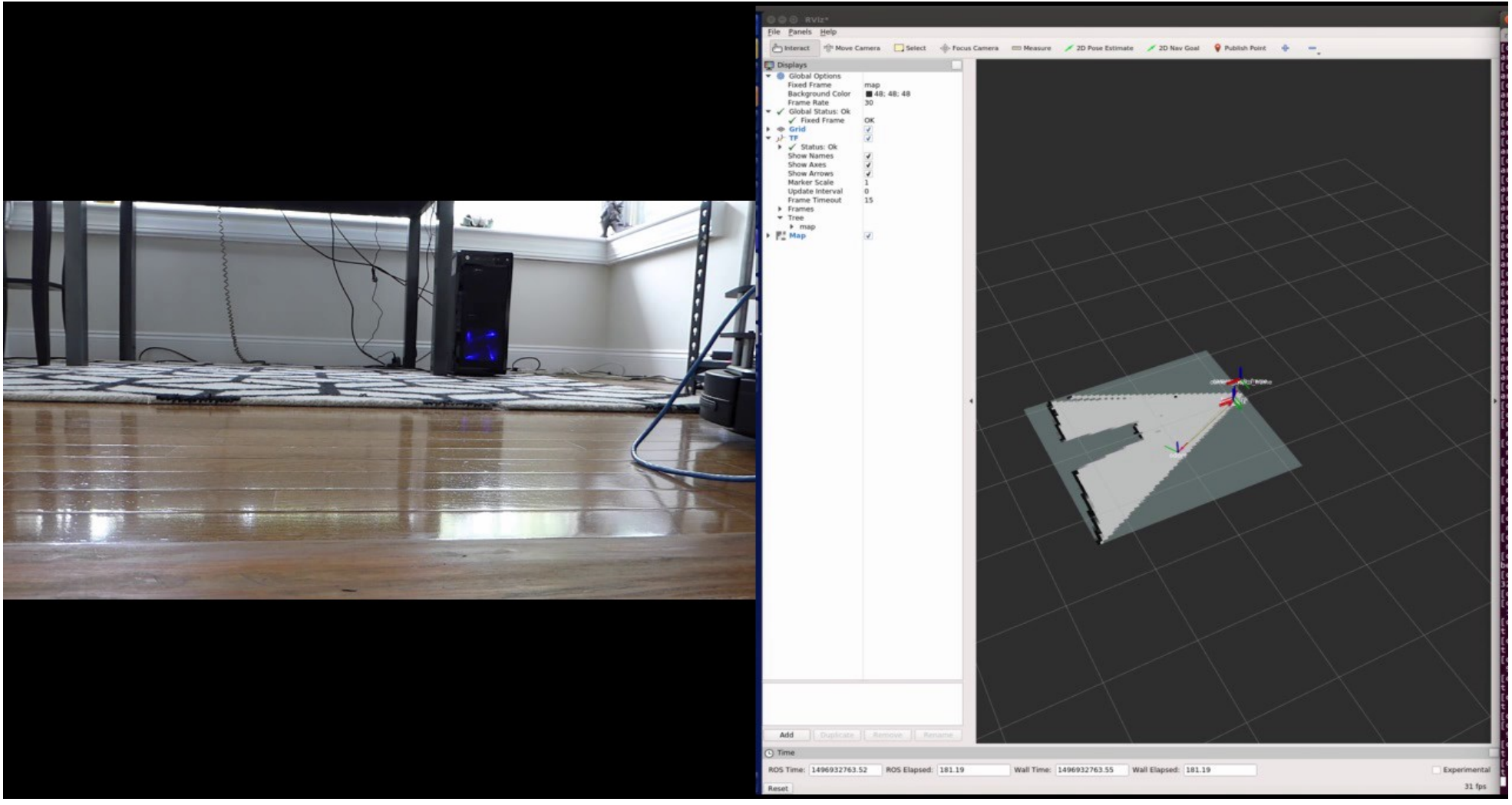


On-robot Software



Off-robot software




RViz*
File Panels Help
Interact
Move Camera
Select
Focus Camera
Measure
2D Pose Estimate
2D Nav Goal
Publish Point
Displays
Global Options
Fixed Frame map
Background Color 48; 48; 48
Frame Rate 30
Global Status: Ok
Fixed Frame OK
Grid
TF
Status: Ok
Show Names
Show Axes
Show Arrows
Marker Scale 1
Update Interval 0
Frame Timeout 15
Frames
Tree
map
Map
Add
Duplicate
Remove
Rename
Time
ROS Time: 1496932763.52
ROS Elapsed: 181.19
Wall Time: 1496932763.55
Wall Elapsed: 181.19
Experimental
Reset
31 fps

More information

Documentation: https://github.com/ros2/turtlebot2_demo

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