

user manual

The manual guides the usage of ROS packages for the XGO-E navigation kit.

ROS package backup location <https://file.hexmove.cn/f/b1482fc3f5fe40eb8598/>

File Locations And Functions

“ **/home/hexman/cartographer_ws** cartographer source file location

/home/hexman/orbbec_ws orbbec_ws

/home/hexman/test_ws/src test_ws/src

--/base base

--/modules modules

--/urdf urdf

--/nav nav

--/src_xpkg_multigoal_plugin rviz

--/xpkg_cartographer/config cartographer

--/bringup demo

--/xpkg_bringup/bringup_camera demo

--/xpkg_bringup/bringup_lidar demo

--/xpkg_bringup/bringup_light demo

--/xpkg_bringup/bringup_vehicle demo

```
--/xpkg_bringup/bringup_nav demo
```

```
--/maps
```

```
--/launch/localization/cartographer launch
```

```
--/launch/planning/move_base launch
```

```
--/config/mark2_mcnm/cartographer movebase
```

The standard Procedure

1. Turn off the remote controller or switch to CAN control mode (please refer to the chassis user manual).
2. Terminal input: `roslaunch xpkg_bringup bringup_cartographer_map.launch`
3. Control movement using the arrow keys on the keyboard in the terminal. Keyboard control has been limited for speed.
4. To save the map, run the following command in a new terminal: `roslaunch xpkg_bringup save_map.sh`. After saving the map, close all terminals.
5. Run the following command in a new terminal: `roslaunch xpkg_bringup bringup_nav_mark2_mcnm.launch`.
6. Plan path points and start navigation using the RViz plugin. [Rviz Plugin usage tutorial](#)

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