

XGO-E

XGO-ETM MARK2TM ORCS-miniTM

- [user manual](#)
- [PDF](#)

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 [] [] [] [] []

/home/hexman/test_ws/src [] [] [] [] [] [] [] [] [] [] []

--/base [] [] [] [] []

--/modules [] [] [] [] []

--/urdf urdf [] []

--/nav [] [] [] [] []

--/src_xpkg_multigoal_plugin rvizUI [] []

--/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](#)



HexagonXGO-EmbeddedROS

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



```
“ /home/hexman/cartographer_ws cartographer

/home/hexman/orbbec_ws 

/home/hexman/test_ws/src 

--/base 

--/modules 

--/urdf urdf

--/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 [ ][ ]unch[ ][ ]

--/launch/planning/move_base [ ][ ]unch[ ][ ]

--/config/mark2_mcnm/cartographer movebase[ ][ ][ ][ ]
```

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--/maps [ ][ ][ ][ ][ ][ ]

--/launch/localization/cartographer [ ][ ]unch[ ][ ]

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--/maps [ ][ ][ ][ ][ ][ ]

--/launch/localization/cartographer [ ][ ]unch[ ][ ]

--/launch/planning/move_base [ ][ ]unch[ ][ ]

--/config/mark2_mcnm/cartographer movebase[ ][ ][ ][ ]
```




```
--/maps [ ][ ][ ][ ][ ][ ]

--/launch/localization/cartographer [ ][ ]unch[ ][ ]

--/launch/planning/move_base [ ][ ]unch[ ][ ]

--/config/mark2_mcnm/cartographer movebase[ ][ ][ ][ ]
```



1. `CAN` 
2. `roslaunch xpkg_bringup bringup_cartographer_map.launch`
3. 
4. `roslrun xpkg_cartographer save_map.sh` 
5. `roslaunch xpkg_bringup bringup_nav_mark2_mcnm.launch`
6. `rviz` `Rviz` 