

Use the STDR simulator to make a map of the provided maze.

Submit a screenshot of your map.

look at your map's .yaml file. Describe what the various values mean.

Move your robot to 3 "interesting" positions in the maze and get its position for each of these poses. Use rostopic echo on the "odom" topic to get these poses.

Submit a screenshot of each of your 3 poses (label them pose1, pose2 and pose3) and include a text file with the corresponding odometry coordinates.

What can you say about coordinates in the map? which way is +x? which is +y? which is heading 0? From your odometry readings, what, approximately, are the dimensions of the maze? What is the resolution of a cell in the map?

p.s.: don't forget you will need to define the base_link:

```
roslaunch static_transform_publisher 0 0 0 0 0 0 1 robot0 base_link 100
```

also, choose a name other than "map" for your new map, e.g.

```
roslaunch map_server map_saver -f stdrMap2 map:=map2
```

also, remap the name of the laser source when doing slam mapping:

```
roslaunch gmapping slam_gmapping scan:=/robot0/laser_0 /map:=/map2
```