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Autonomous navigation of a Turtlebot robot with ROS 2

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This project presents an autonomous navigation system for a TurtleBot3 using ROS 2 (Jazzy Jalisco distribution). The approach combines SLAM, localization algorithms and a reactive obstacle avoidance method based on potential fields, enabling real-time navigation without human intervention. A leader-follower application is proposed to apply the described methods.

Master

Laboratoire d'accueil

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