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| Task. No.: | 6 | Points: | 5 | TurtleBot3 Obstacle avoidance |

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| Objectives:  1. Working with other message types. 2. Using ROS services. |

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| Description: The goal of this exercise is to navigate TurtleBot to a predefined location and avoid obstacle collision. This is the extension of the exercise 5. |

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| Step | Action |
| 1 | Find obstacles around TurtleBot by subscribing the laser scan topic, which gives the obstacle range around the robot.  The topic is */scan* and the message type is *sensor\_msgs/LaserScan*. |
| 2 | Get all the fields inside this message by using the following command.  $ rosmsg show sensor_msgs/LaserScan |
| 3 | Change the *move\_turtlebot.py* file in the previous exercise. Use ROS **service** instead of **topic**. |

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