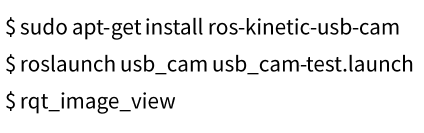
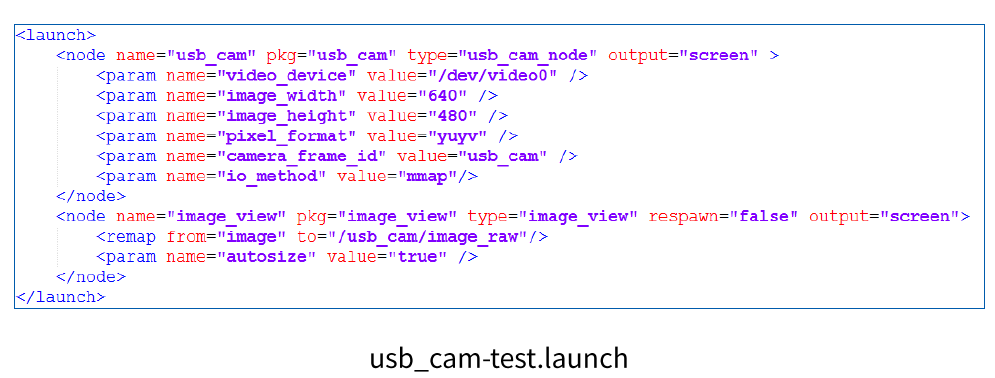
3.ros机器人系统设计

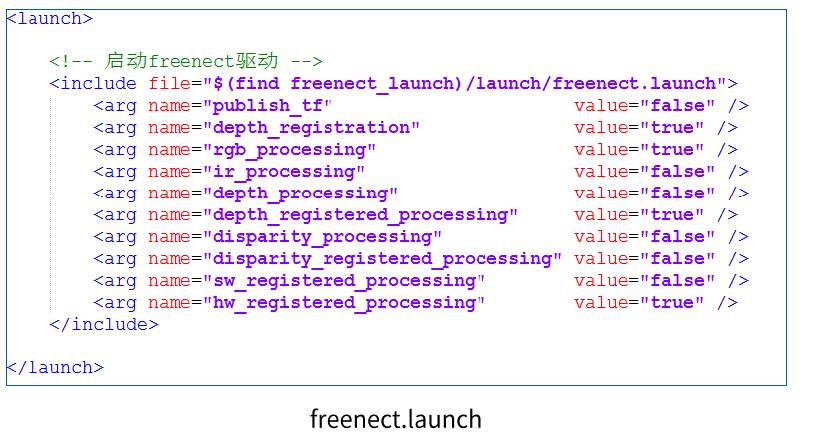
1.连接摄像头



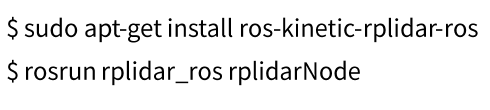


2.连接Kinect



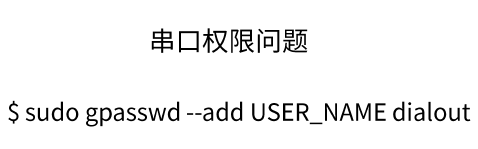


3.连接激光雷达



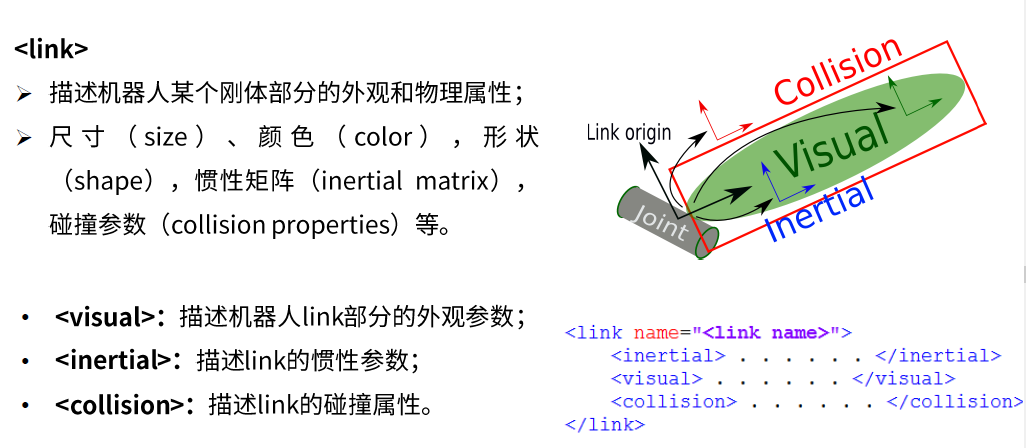
启动rplidar激光雷达

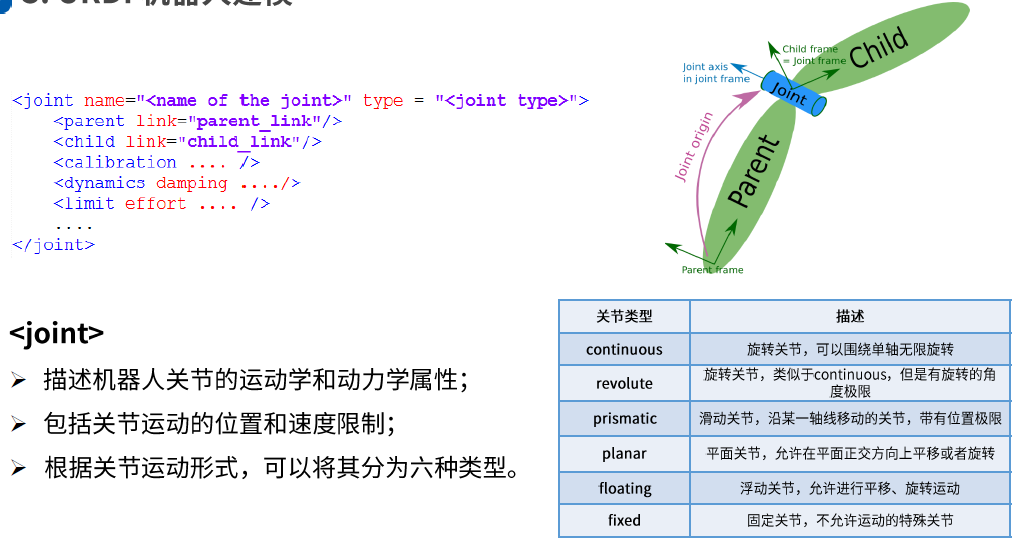
rosrun rplidar\_ros rpliderNode

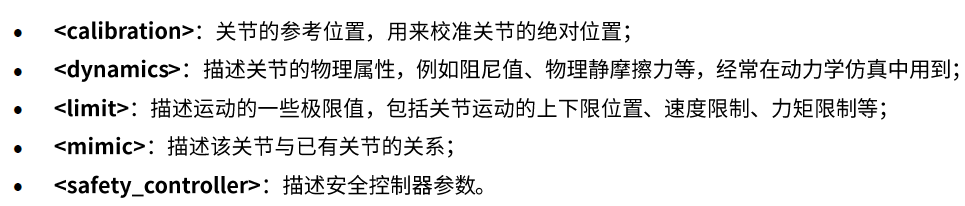


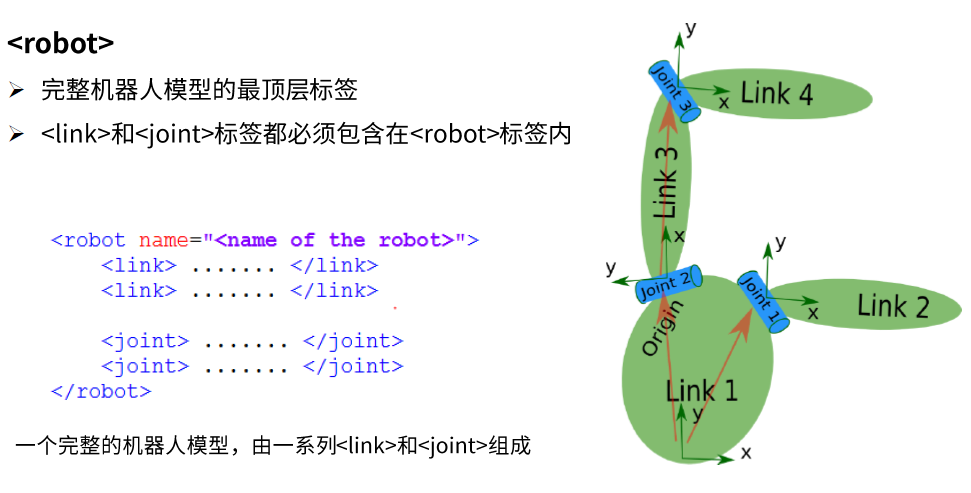
监听雷达信息 rostpic echo /scan

4.URDF机器人建模









5.创建一个机器人建模的功能包



