

姓名：王伟皓 学号：11612010

队友：姓名：孙耀威 学号：11610326

/camera/rgb/image_color:

从 Kinect 读取的彩色图的数据。

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Kinect 读取的深度图的数据。

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单色未调整的图像数据。

| | | | | | | | | | | | | | | | | | | | | | |
|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|-----|
| 185, | 184, | 182, | 184, | 185, | 184, | 183, | 182, | 183, | 182, | 182, | 182, | 183, | 182, | 183, | 184, | 171, | 118 | | | | |
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对机器人的位置和速度的估计值。

```

---
header:
  seq: 43514
  stamp:
    secs: 1553931512
    nsecs: 295421877
  frame_id: "odom"
child_frame_id: "base_footprint"
pose:
  pose:
    position:
      x: 0.129192725568
      y: 0.25025355588
      z: 0.0
    orientation:
      x: 0.0
      y: 0.0
      z: -0.275805123434
      w: 0.961213573504
  covariance: [0.1, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.1, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 10000
000000.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 100000000000.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 10000
000000.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.05]
twist:
  twist:
    linear:
      x: 0.0
      y: 0.0
      z: 0.0
    angular:
      x: 0.0
      y: 0.0
      z: 0.0331612557879
  covariance: [0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0,
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0.0, 0.0, 0.0]
---

```

/tf

机器人的位置信息。

```

---
transforms:
-
  header:
    seq: 0
    stamp:
      secs: 1553932078
      nsecs: 283154938
    frame_id: "odom"
  child_frame_id: "base_footprint"
  transform:
    translation:
      x: -0.154049816895
      y: -0.0553803853187
      z: 0.0
    rotation:
      x: 0.0
      y: 0.0
      z: 0.0584352225182
      w: 0.99829120239
---

```

/tf_static

与/tf 中的数据格式一样，但/tf_static 的数据永远不会改变。

```
-
  header:
    seq: 0
    stamp:
      secs: 1553930640
      nsecs: 741763873
    frame_id: "base_link"
  child_frame_id: "pole_bottom_1_link"
  transform:
    translation:
      x: 0.055
      y: 0.12
      z: 0.1028
    rotation:
      x: 0.0
      y: 0.0
      z: 0.0
      w: 1.0
-
```

/camera/rgb/image_color_view:

从 kinect 获得的图像.



/camera/depth_registered/image_raw _view
从 kinect 获得的深度图。

