NAVIGATION CHALLENGE			
Descrizione	**Nome Topic**	**Type**	**Frequenza Media**
Topic laserscan del Lidar	*/scan*	*sensor_msgs/LaserScan*	*9.5 Hz*
Topic pointcloud del Lidar	*/points_raw*	*sensor_msgs/PointCloud2*	*8 Hz*
Topic per comandare robot ad alto livello	*/cmd_vel*	*geometry_msgs/Twist*	*10000 Hz (MAX)*
Topic per dati IMU	*/imu_raw*	*sensor_msgs/Imu*	*470 Hz*
Topic per dati Odometry	*/odometry/imu*	*nav_msgs/Odometry*	*470 Hz*
Topic per dynamic TF	*/tf*	*Tf2_msgs/TFMessage*	*955 Hz*
Topic per static TF	*/tf_static*	*Tf2_msgs/TFMessage*	
Topic della camera RealSense	*/camera/color/image_raw*	*sensor_msgs/Image*	*15 fps (resolution 640x480)*
Topics delle camere laterali di sinistra del robot	*/camera/left/left/image_raw* */camera/left/right/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*13 fps (resolution 928x400)*
Topics delle camere laterali di destra del robot	*/camera/right/left/image_raw* */camera/right/right/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*13 fps (resolution 928x400)*
Topics delle camere posteriori sotto il body del robot	*/camera_rearDown/left/image_raw* */camera_rearDown/right/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*30 fps (resolution 928x400)*
Topics delle camere anteriori sotto la testa del robot	*/camera/chin_left/image_raw* */camera/chin_right/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*13 fps (resolution 928x400)*

Topics delle camere frontali del robot	*/camera/front_left/image_raw* */camera/front_right/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*13 fps (resolution 928x400)*

LOCOMOTION CHALLENGE			
Descrizione	**Nome Topic**	**Type**	**Frequenza Media**
Topic per Low level telemetry	*/low_state*	*unitree_legged_msgs/LowState* ***	*500 Hz (MAX)*
Topic per Low level command	*/low_cmd*	*unitree_legged_msgs/LowCmd* ***	*10000 Hz (MAX)*
Topic laserscan del Lidar	*/scan*	*sensor_msgs/LaserScan*	*9.5 Hz*
Topic pointcloud del Lidar	*/points_raw*	*sensor_msgs/PointCloud2*	*8 Hz*
Topic per static TF	*/tf_static*	*Tf2_msgs/TFMessage*	
Topic della camera RealSense	*/camera/color/image_raw*	*sensor_msgs/Image*	*15 fps (resolution 640x480)*
Topics delle camere laterali di sinistra del robot	*/camera/left/left/image_raw* */camera/left/right/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*13 fps (resolution 928x400)*
Topics delle camere laterali di destra del robot	*/camera/right/left/image_raw* */camera/right/right/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*13 fps (resolution 928x400)*
Topics delle camere posteriori sotto il	*/camera_rearDown/left/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*30 fps (resolution 928x400)*

body del robot	*/camera_rearDown/right/image_raw*		
Topics delle camere anteriori sotto la testa del robot	*/camera/chin_left/image_raw* */camera/chin_right/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*13 fps (resolution 928x400)*
Topics delle camere frontali del robot	*/camera/front_left/image_raw* */camera/front_right/image_raw*	*sensor_msgs/Image* *sensor_msgs/Image*	*13 fps (resolution 928x400)*

***** https://github.com/unitreerobotics/unitree_ros_to_real/tree/master/unitree_legged_msgs/msg

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