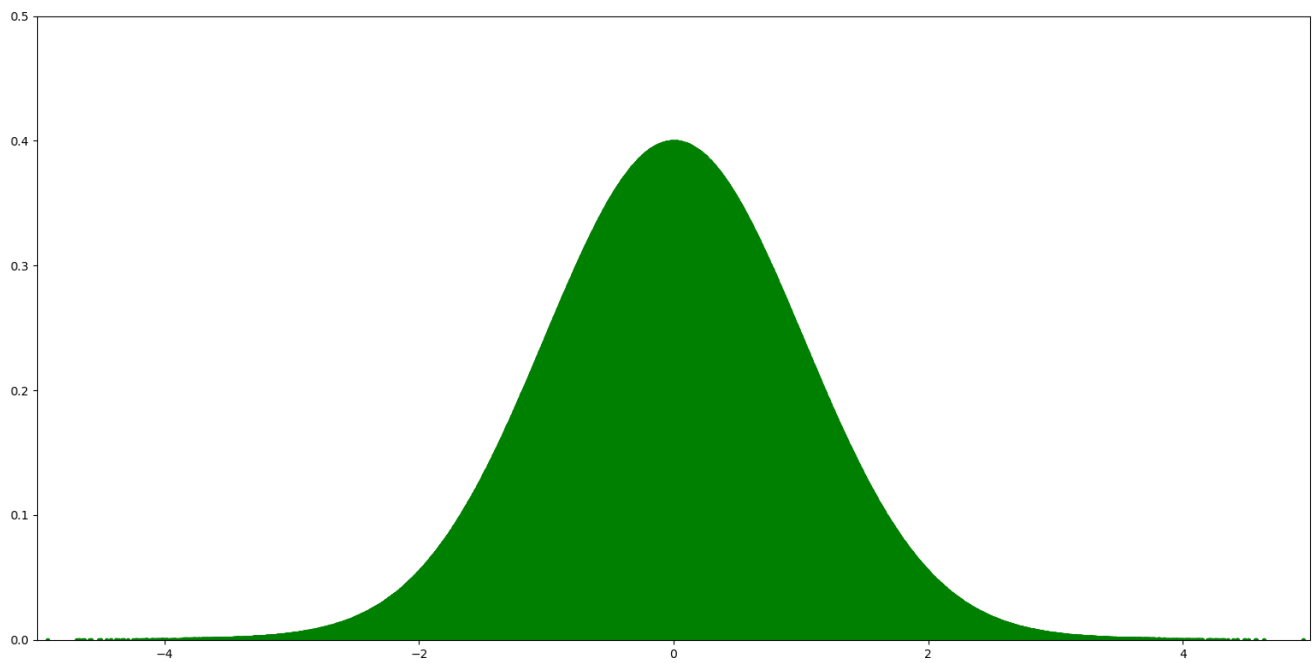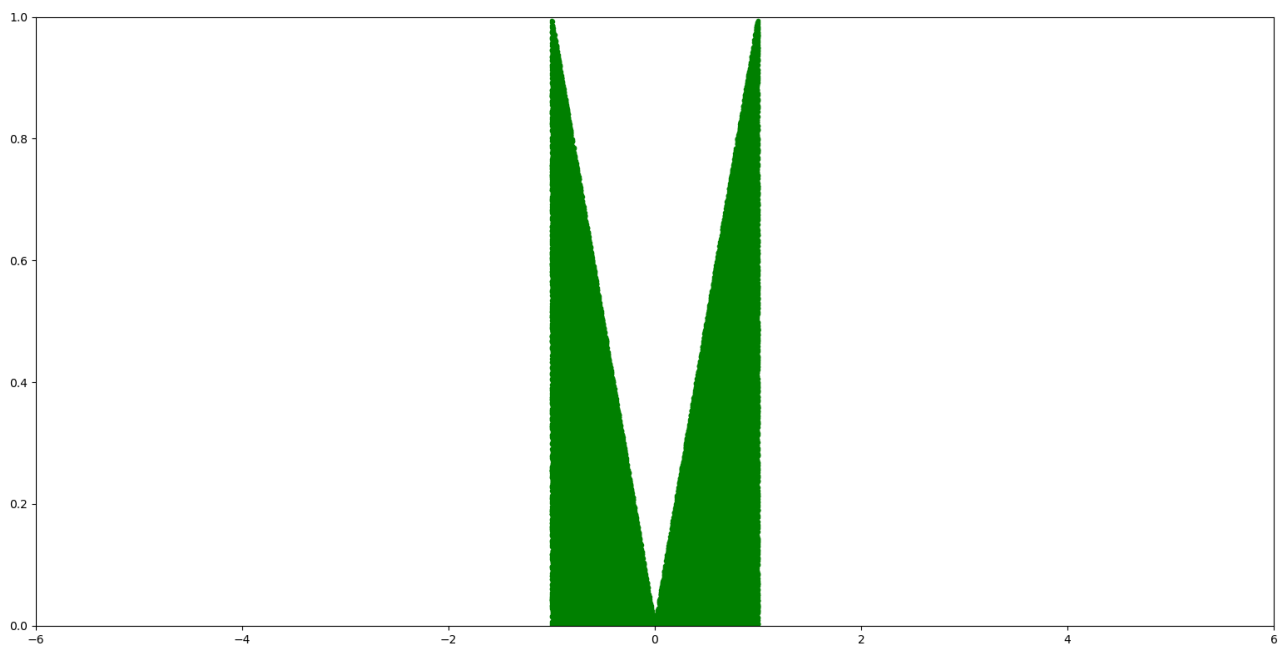# Q1

Normal:

abs:

triangular:
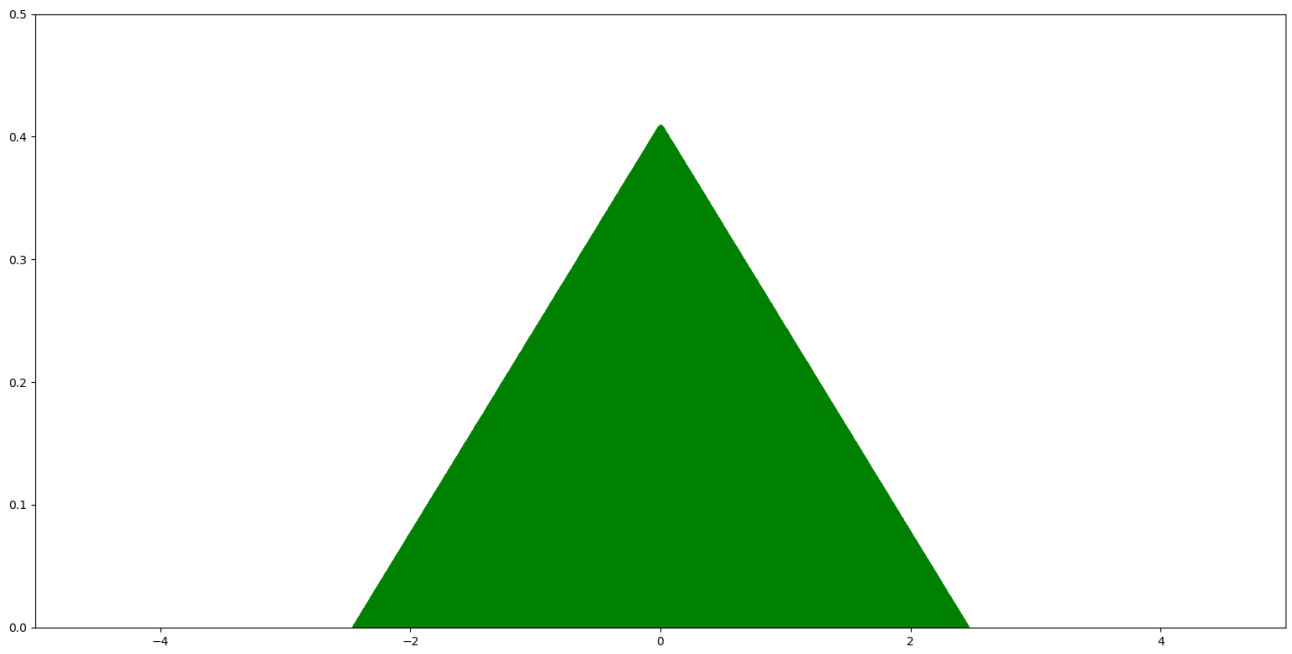
Q2

odometry based:

Q3
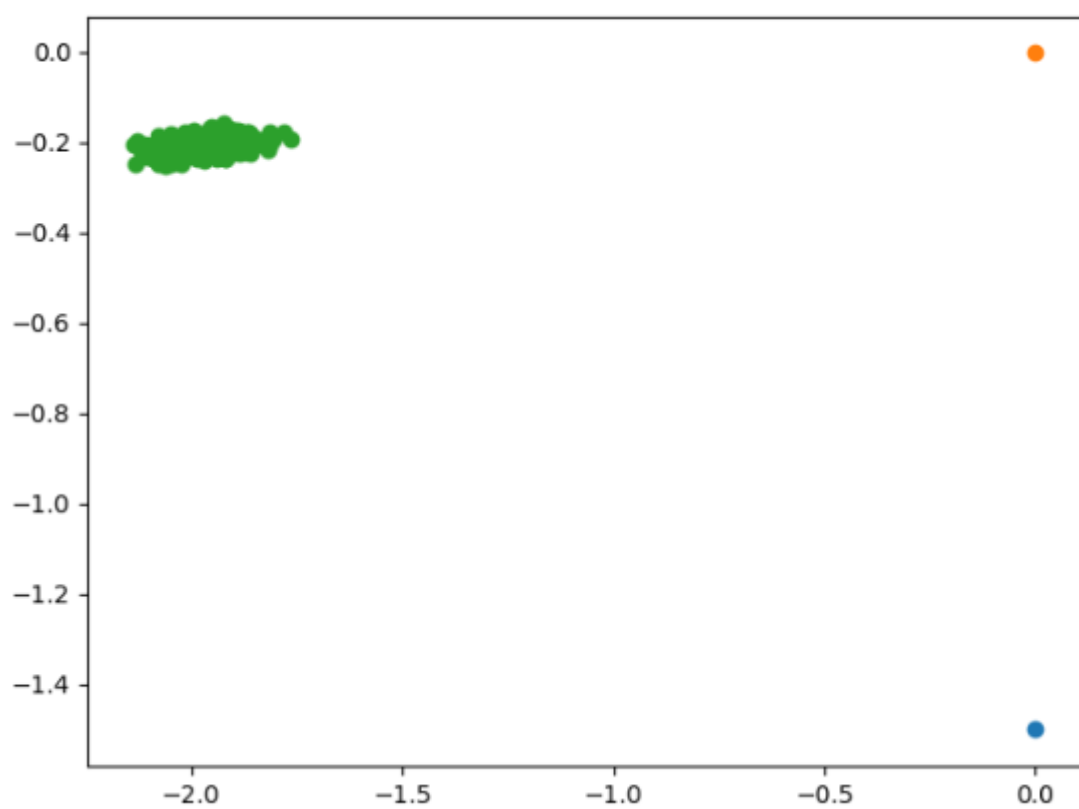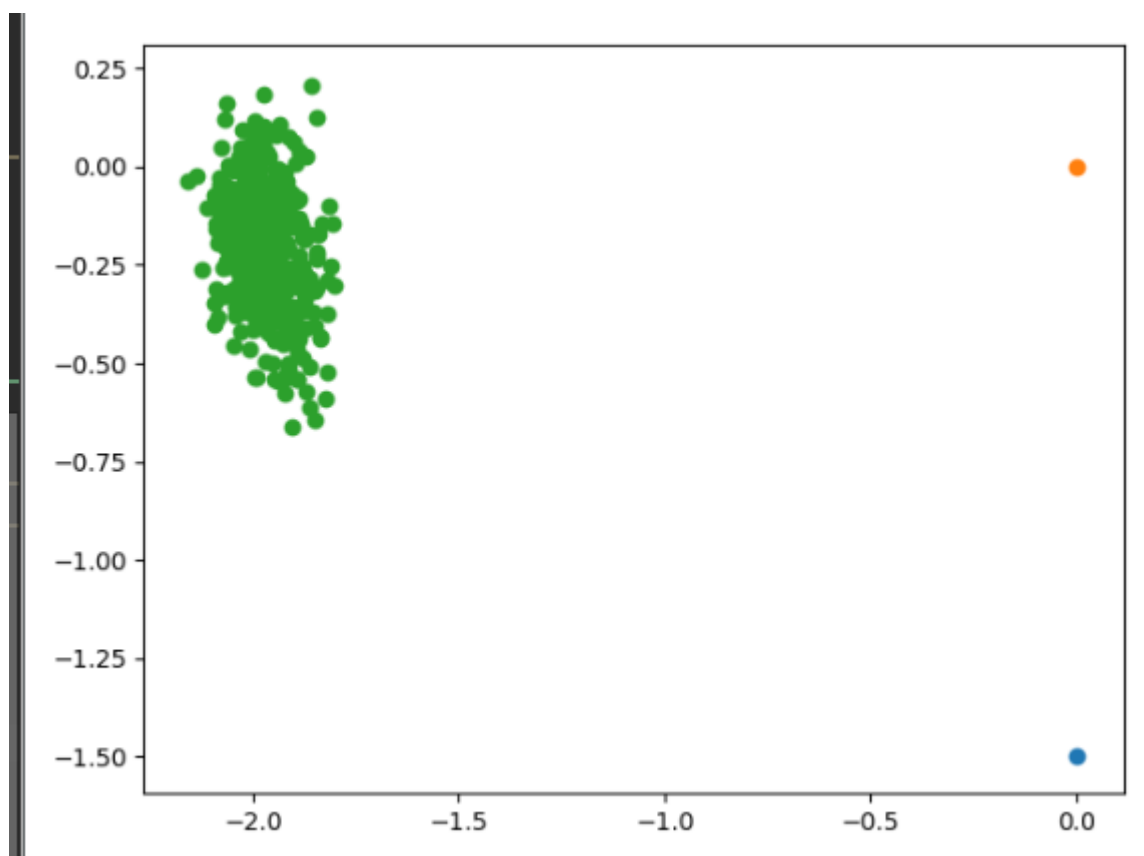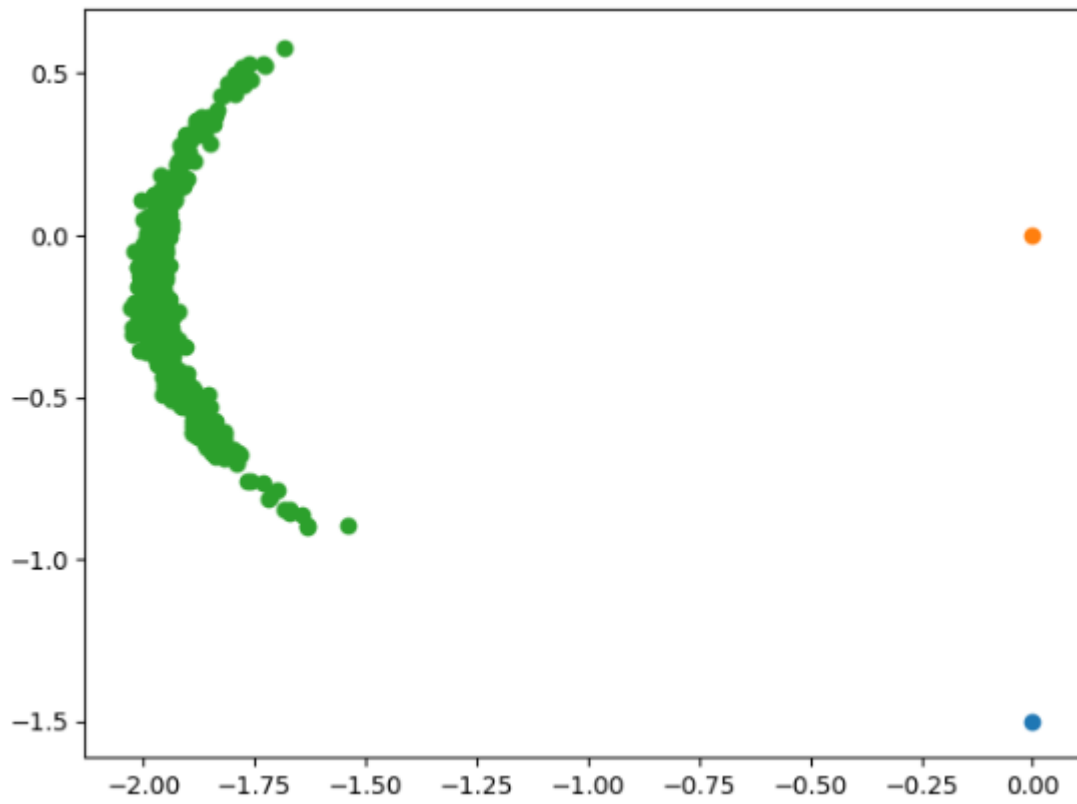
Q4
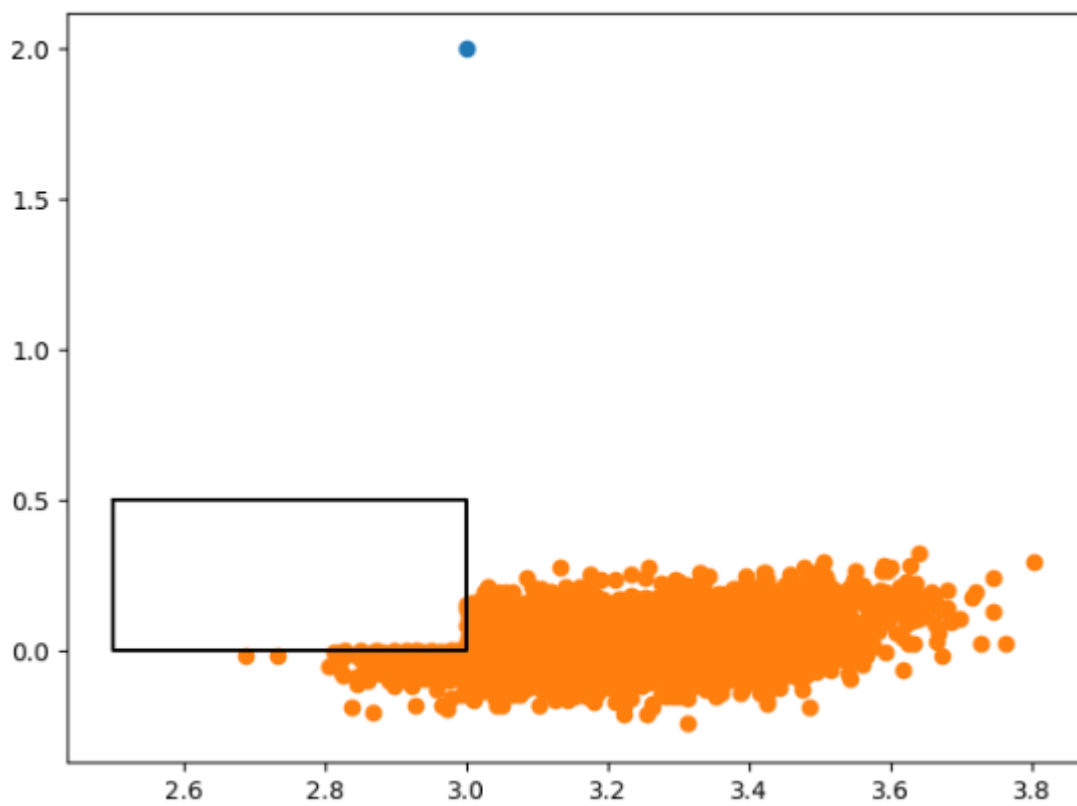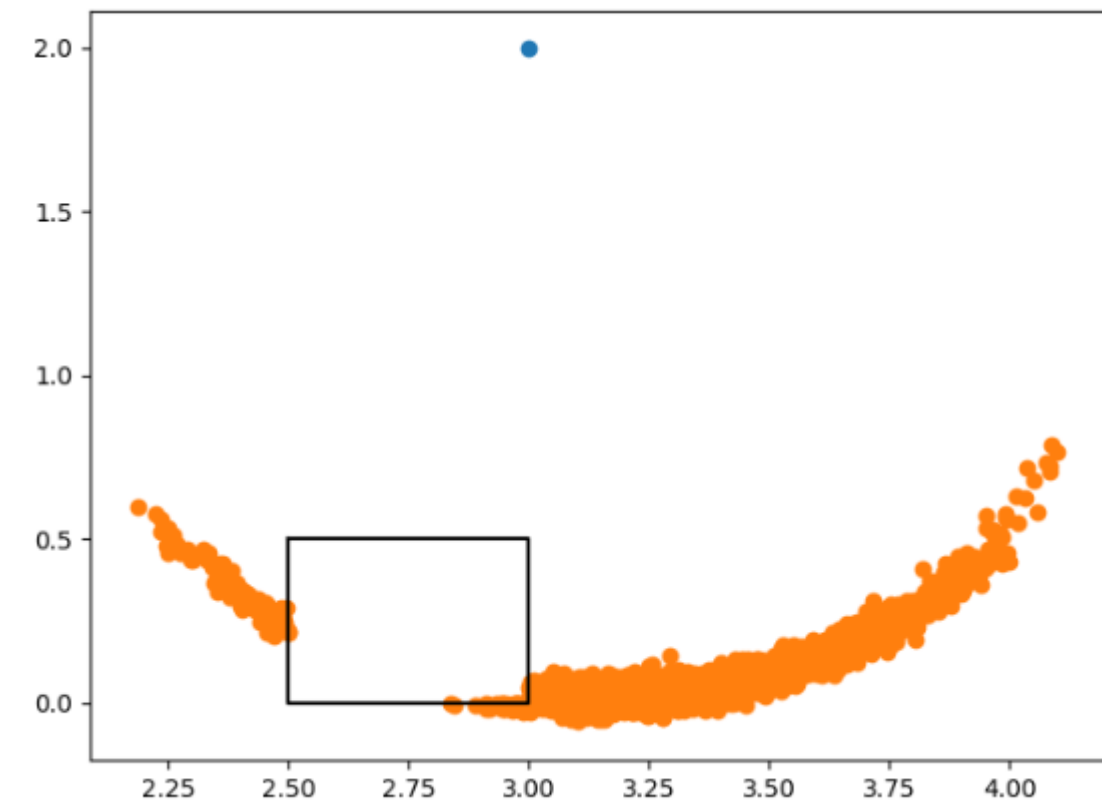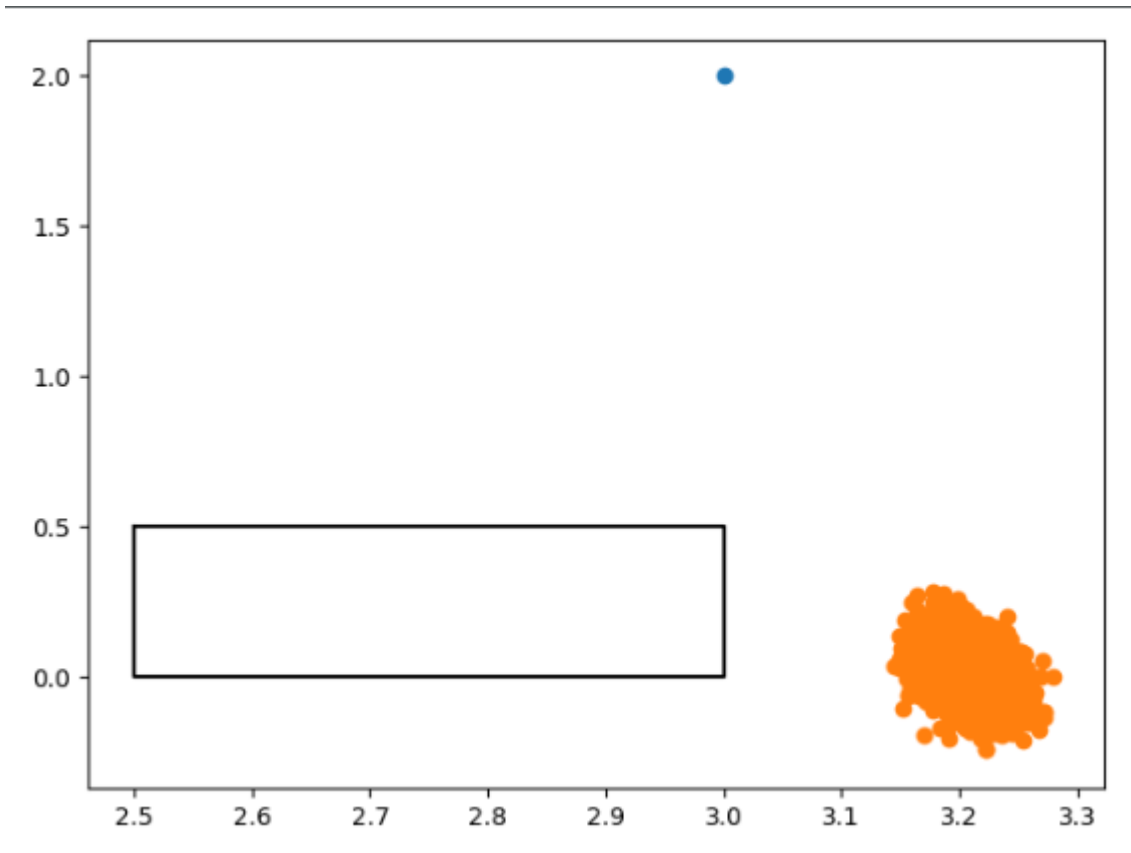
Lab

my: 11610127 郑浩

partner: 11610226 吕俊延

View ros topic:

rostopic echo tf:

rostopic echo tf_static:

rostopic echo camera/depth_registered/image_raw:

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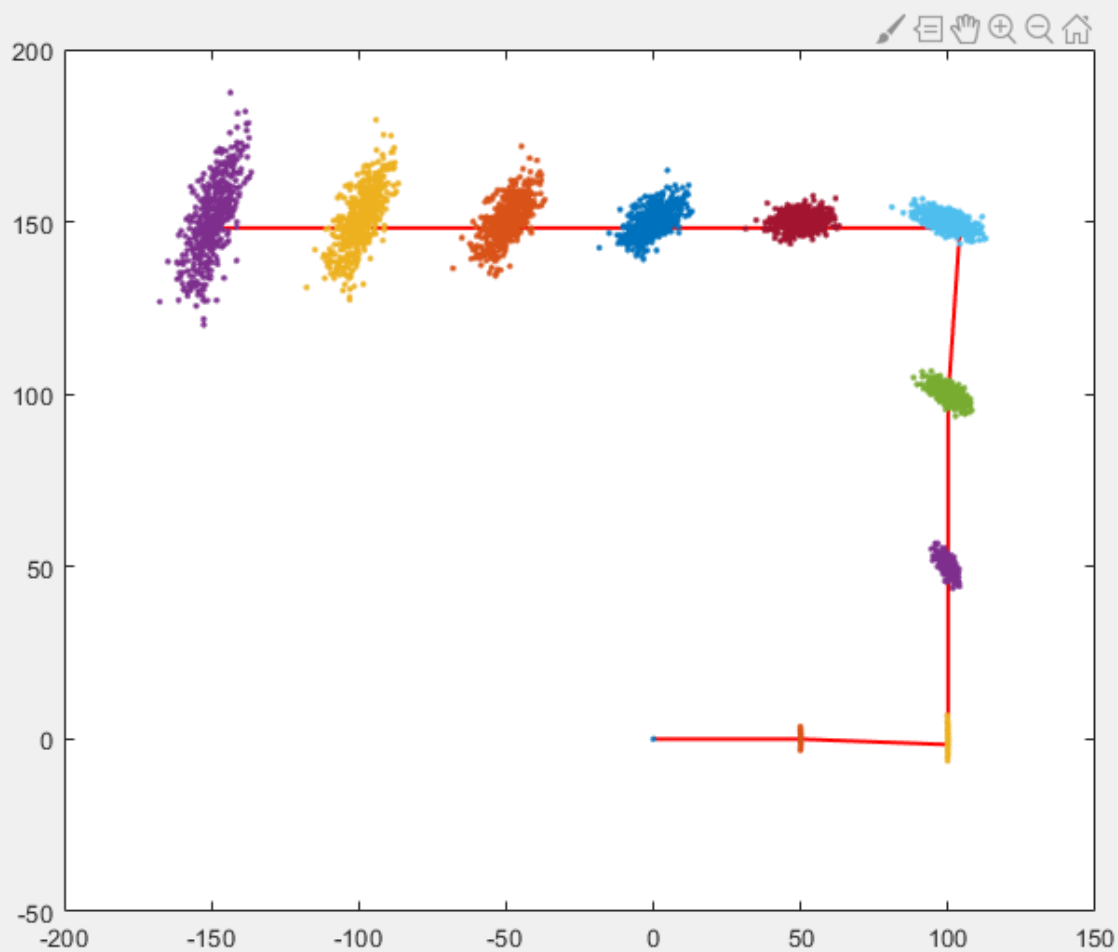0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0,
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`rostopic echo camera/rgb/image_color:`

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Explanation: The number is the RGB number of image.

`rostopic echo odom:`

Explanation: The odometry value of robot from time to time.

`rostopic echo rosout`:

View camera topics:

mono:

depth:

color: