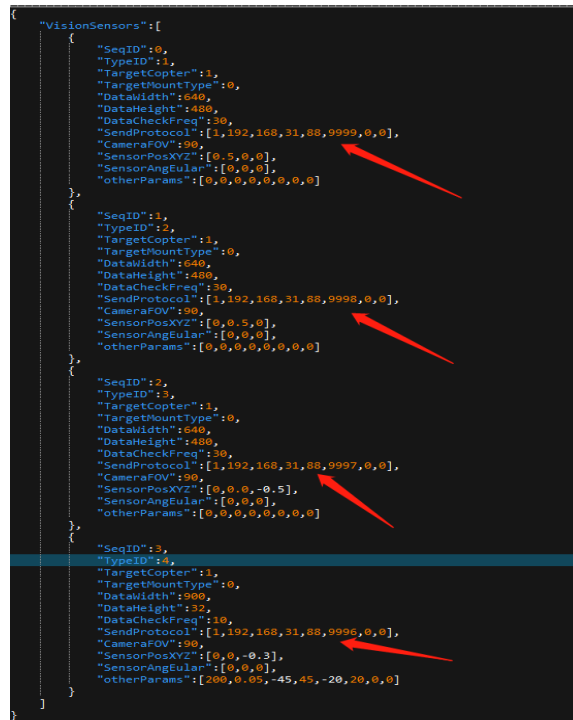


环境配置：只要使用以前的 ubuntu 镜像即可，

参数配置：将里面所有的 IP 改成自己的虚拟机内 Ubuntu ip(在 ubuntu 内打开终端输入：ifconfig 查看)



```

"VisionSensors": [
  {
    "SeqID": 0,
    "TypeID": 11,
    "TargetCopter": 1,
    "TargetMountType": 0,
    "DataWidth": 640,
    "DataHeight": 480,
    "DataCheckFreq": 30,
    "SendProtocol": [1, 192, 168, 31, 88, 9999, 0, 0],
    "CameraFOV": 90,
    "SensorPosXYZ": [0, 5, 0, 0],
    "SensorAngular": [0, 0, 0],
    "OtherParams": [0, 0, 0, 0, 0, 0, 0]
  },
  {
    "SeqID": 1,
    "TypeID": 12,
    "TargetCopter": 1,
    "TargetMountType": 0,
    "DataWidth": 640,
    "DataHeight": 480,
    "DataCheckFreq": 30,
    "SendProtocol": [1, 192, 168, 31, 88, 9998, 0, 0],
    "CameraFOV": 90,
    "SensorPosXYZ": [0, 0, 5, 0],
    "SensorAngular": [0, 0, 0],
    "OtherParams": [0, 0, 0, 0, 0, 0, 0]
  },
  {
    "SeqID": 2,
    "TypeID": 3,
    "TargetCopter": 1,
    "TargetMountType": 0,
    "DataWidth": 640,
    "DataHeight": 480,
    "DataCheckFreq": 30,
    "SendProtocol": [1, 192, 168, 31, 88, 9997, 0, 0],
    "CameraFOV": 90,
    "SensorPosXYZ": [0, 0, 0, -0.5],
    "SensorAngular": [0, 0, 0],
    "OtherParams": [0, 0, 0, 0, 0, 0, 0]
  },
  {
    "SeqID": 3,
    "TypeID": 14,
    "TargetCopter": 1,
    "TargetMountType": 0,
    "DataWidth": 960,
    "DataHeight": 32,
    "DataCheckFreq": 10,
    "SendProtocol": [1, 192, 168, 31, 88, 9996, 0, 0],
    "CameraFOV": 90,
    "SensorPosXYZ": [0, 0, -0.3],
    "SensorAngular": [0, 0, 0],
    "OtherParams": [200, 0.05, -45, 45, -20, 20, 0, 0]
  }
]

```

同时修改 server_ue4.py 文件中 vis.RemotSendIP 的值，改成自己的虚拟机 IP

```
vis.RemotSendIP = "192.168.31.88"
```

运行步骤：

1. 右键管理员身份运行 RunRflysim3DSITL.bat
2. 在 windows 下运行 pthon client_ue4.py
3. 在 Ubuntu 下打开终端运行 roscore，再另开终端运行 python3 server_ue4.py
4. 运行 rviz->点击 左上角 file 选择当前目录下的 vision.rviz 配置文件，就能看到效果

图中的结果

过程结果说明：当运行 python3 server_ue4.py 之后能看到以下话题

```
wsh@ubuntu:~/VisCaptureMergeROSAPI
File Edit View Search Terminal Tabs Help
roscore http://ubuntu:11... x python3 server_ue4.py x wsh@ubuntu:~/VisCaptur... x
→ VisCaptureMergeROSAPI rostopic list
/rflysim/imu
/rosout
/rosout_agg
/sensor0/img_rgb
/sensor1/img_depth
/sensor2/img_gray
/sensor3/vehicle_lidar
→ VisCaptureMergeROSAPI
```

效果展示：其中有激光点云，有彩色图，有灰度图，有深度图

