

Lab 3

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实验内容：

Transform Configuration（变换配置）

实验截图：

重新设置后，相应的传感器的y方向距离机体基准偏移10cm，z方向20cm, x方向为0。

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liuyue@liuyue-Lenovo-G470: ~/catkin_ws
(1.10, 0.20, 0.20) at time 1523351399.61
[ INFO] [1523351409.846528698]: base_laser: (1.00, 0.20, 0.00) -----> base_link:
(1.10, 0.20, 0.20) at time 1523351399.61
[ INFO] [1523351410.846202797]: base_laser: (1.00, 0.20, 0.00) -----> base_link:
(1.10, 0.20, 0.20) at time 1523351399.61
[ INFO] [1523351411.846903721]: base_laser: (1.00, 0.20, 0.00) -----> base_link:
(1.10, 0.20, 0.20) at time 1523351399.61
[ INFO] [1523351412.846449434]: base_laser: (1.00, 0.20, 0.00) -----> base_link:
(1.10, 0.20, 0.20) at time 1523351399.61
^C[ INFO] [1523351413.847069673]: base_laser: (1.00, 0.20, 0.00) -----> base_link:
(1.10, 0.20, 0.20) at time 1523351399.61
liuyue@liuyue-Lenovo-G470:~/catkin_ws$ rosrun robot_setup_tf tf_listener
[ INFO] [1523351418.463971124]: base_laser: (1.00, 1.20, 1.00) -----> base_link:
(1.00, 1.30, 1.20) at time 1523351418.46
[ INFO] [1523351419.463669222]: base_laser: (1.00, 1.20, 1.00) -----> base_link:
(1.00, 1.30, 1.20) at time 1523351419.46
[ INFO] [1523351420.464302147]: base_laser: (1.00, 1.20, 1.00) -----> base_link:
(1.00, 1.30, 1.20) at time 1523351420.46
[ INFO] [1523351421.464252458]: base_laser: (1.00, 1.20, 1.00) -----> base_link:
(1.00, 1.30, 1.20) at time 1523351421.46
[ INFO] [1523351422.463925884]: base_laser: (1.00, 1.20, 1.00) -----> base_link:
(1.00, 1.30, 1.20) at time 1523351422.46
[ INFO] [1523351423.463654092]: base_laser: (1.00, 1.20, 1.00) -----> base_link:
(1.00, 1.30, 1.20) at time 1523351423.46
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