

## 示例6——目标跟踪

### 机器人端（SSH登录）：

#### 1、启动底盘

```
roslaunch gohi_hw gohi_hw.launch
```

#### 2、启动kinect

```
roslaunch openni_launch openni.launch
```

#### 3、启动自适应人体跟踪

```
roslaunch track_pkg kcf_node
```

### 机器人端（SSH登录）：

#### 1、启动底盘

```
roslaunch gohi_hw gohi_hw.launch
```

#### 2、启动kinect

```
roslaunch openni_launch openni.launch
```

#### 3、启动任意目标跟踪

```
roslaunch tracker_kcf_ros kcf_node_all
```