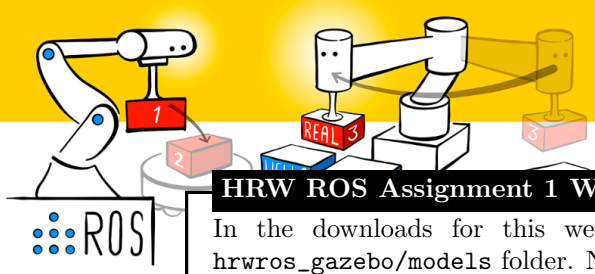

HRW ROS Assignment 1 Week 5 Part 1

In the downloads for this week, the two logical camera models have been included in the `hrwros_gazebo/models` folder. Namely `logical_camera1` and `logical_camera2`.

In the first part of this assignment, you will have to add these two logical cameras to a new world file named `week5_assignment1.world`, located on the `hrwros_gazebo/worlds` folder.

The poses for the logical camera models are:

Pose for logical camera 1: `1.2 1.8 2.0 0 1.57 0`
Pose for logical camera 2: `-8.3 -1.23 1.8 0 1.57 0`

HRW ROS Assignment 1 Week 5 Part 2

Just adding the cameras is not sufficient because we cannot use them without configuring them.

In this part we will configure them. You will have to update the `model.sdf` files in the folders for each logical camera wherever you are instructed to `<write_code_here>`.

The following configuration parameters are desired:

Configuration for Logical Camera 1:

Model name: `logical_camera_1`
Link name: `logical_camera_1_link`
Sensor name: `logical_camera_1`

Configuration for Logical Camera 2:

Model name: `logical_camera_2`
Link name: `logical_camera_2_link`
Sensor name: `logical_camera_2`

After you have completed the sdf files with the above configurations, start the factory simulation with:

```
$ roslaunch hrwros_week5 week5_assignment1.launch
```

Also recommended is to just verify if you receive the relevant topics related to the Logical cameras you just installed with `rostopic list`.
Recall from Video 5.1.2, what names do the Logical camera topics take. And also use tools you have learned from first week like `rostopic info`.

This completes HRW ROS Assignment 1 Week 5