

Deliverable 1

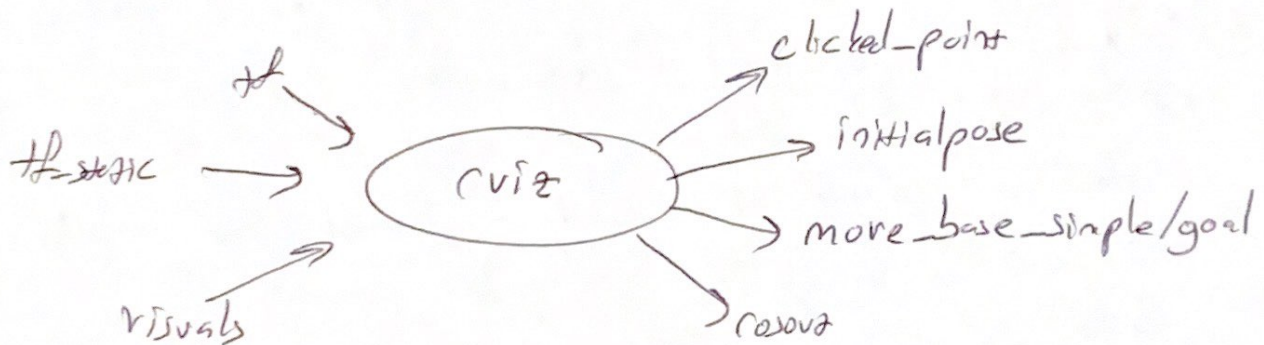
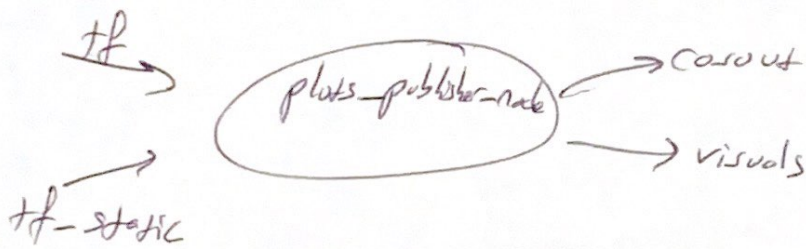
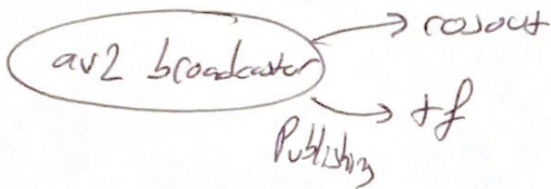
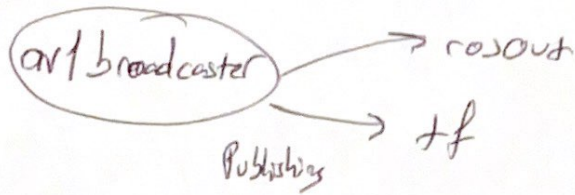
Q1) Using "roscat list" ;

- av1broadcaster
- av2broadcaster
- plots_publisher_node
- rosout
- rviz

Q2) I could have run every node separately using "roscat", I would not need to run "rosout", so I need to use "roscat" 4 times and I would need to use "roscat" to create a master in the first terminal, so I would need to use 5 terminals,

- roscore
- roscat two_drones_pkgs av1broadcaster
- " " av2broadcaster
- " " rviz
- " " plots_publisher_node

Q3)



→ av1broadcaster and av2broadcaster publishing rv1, av2, frames.

→ "visuals" topic is causing rviz to plot the drone motion.

Q4) When we use the "static:=True", launch file has its own static descriptions for the positions of the drone and it visualizes them directly. When we take this term off, launch file is directing to "plots-publisher-node" and "frames-publisher-node" files to describe rotation and positions of the drones.