gazebo发布的ros话题接口

ros_master_uri

http://cloud_ip_address:11311
cloud_ip_address 以后续仿真平台运行的云服务器ip地址为准。

车的6dof位姿

1. ros topic名称：
   /ground_truth/robot_state
2. ros_message文件：
   /ground_truth/robot_state话题发布的gazebo_msgs/ModelState.msg数据结构：
   string model_name # model to set state (pose and twist)
   geometry_msgs/Pose pose # desired pose in reference frame
   geometry_msgs/Twist twist # desired twist in reference frame
   string reference_frame # set pose/twist relative to the frame of this entity (Body/Model)
   # leave empty or "world" or "map" defaults to world-frame

zed双目相机

1. ros topic名称(最主要的加粗显示)：
   /stereocamera/left/camera_info
   /stereocamera/left/image_raw
   /stereocamera/left/image_raw/compressed
   /stereocamera/left/image_raw/compressed/parameter_descriptions
   /stereocamera/left/image_raw/compressed/parameter_updates
   /stereocamera/left/image_raw/compressedDepth
   /stereocamera/left/image_raw/compressedDepth/parameter_descriptions
   /stereocamera/left/image_raw/compressedDepth/parameter_updates
   /stereocamera/left/image_raw/theora
   /stereocamera/left/image_raw/theora/parameter_descriptions
   /stereocamera/left/image_raw/theora/parameter_updates
   /stereocamera/left/parameter_descriptions
   /stereocamera/left/parameter_updates

/stereocamera/right/camera_info
/stereocamera/right/image_raw
/stereocamera/right/image_raw/compressed
/stereocamera/right/image_raw/compressed/parameter_descriptions
/stereocamera/right/image_raw/compressed/parameter_updates
/stereocamera/right/image_raw/compressedDepth
/stereocamera/right/image_raw/compressedDepth/parameter_descriptions
/stereocamera/right/image_raw/compressedDepth/parameter_updates
/stereocamera/right/image_raw/theora
/stereocamera/right/image_raw/theora/parameter_descriptions
/stereocamera/right/image_raw/theora/parameter_updates
/stereocamera/right/parameter_descriptions
/stereocamera/right/parameter_updates

2. ros_message文件：

- .../camera_info话题发布的sensor_msgs/CameraInfo.msg数据结构：
  std_msgs/Header header
  uint32 height
  uint32 width
  string distortion_model
  float64[] D
  float64[9] K
  float64[9] R
  float64[12] P
  uint32 binning_x
  uint32 binning_y
  sensor_msgs/RegionOfInterest roi
- .../image_raw话题发布的sensor_msgs/Image数据结构：
  std_msgs/Header header
  uint32 height
  uint32 width
  string encoding
  uint8 is_bigendian
  uint32 step
  uint8[] data
- .../image_raw/compressed话题发布的sensor_msgs/CompressedImage.msg数据结构：
  std_msgs/Header header
  string format
  uint8[] data

Kinect相机

1. ros topic名称(最主要的加粗显示)：
   /camera/depth/camera_info//传输深度相机内参
   /camera/depth/image_raw //传输depth图
   /camera/rgb/camera_info//传输rgb相机内参
   /camera/rgb/image_raw //传输rgb图
   /camera/rgb/image_raw/compressed//传输压缩过的rgb图
   /camera/rgb/image_raw/compressed/parameter_descriptions
   /camera/rgb/image_raw/compressed/parameter_updates
   /camera/rgb/image_raw/compressedDepth
   /camera/rgb/image_raw/compressedDepth/parameter_descriptions
   /camera/rgb/image_raw/compressedDepth/parameter_updates
   /camera/rgb/image_raw/theora
   /camera/rgb/image_raw/theora/parameter_descriptions
   /camera/rgb/image_raw/theora/parameter_updates
2. ros_message文件见zed双目相机的介绍

激光ladar

Imu

1. ros topic名称(最主要的加粗显示)
   /imu/data
   /imu/data/accel/parameter_descriptions
   /imu/data/accel/parameter_updates
   /imu/data/bias
   /imu/data/rate/parameter_descriptions
   /imu/data/rate/parameter_updates
   /imu/data/yaw/parameter_descriptions
   /imu/data/yaw/parameter_updates
2. ros_message文件：

- /imu/data话题发布的sensor_msgs/Imu.msg数据结构：
  std_msgs/Header header
  geometry_msgs/Quaternion orientation
  float64[9] orientation_covariance
  geometry_msgs/Vector3 angular_velocity

float64[9] angular_velocity_covariance
geometry_msgs/Vector3 linear_acceleration
float64[9] linear_acceleration_covariance