

## Anzeigen der Octomap in RVIZ2:

- Octomap-Server installieren:

sudo apt install ros-humble-octomap-server

- Im Ordner emr2 / launch eine neue Datei

octomap\_server.launch.py anlegen:

```
octomap_server.launch.py
1 from launch import LaunchDescription
2 from launch_ros.actions import Node
3
4 def generate_launch_description():
5     return LaunchDescription([
6         Node(
7             package='octomap_server',
8             executable='octomap_server_node',
9             name='octomap_server',
10            output='screen',
11            parameters=[
12                {'resolution':0.05},
13                {'frame_id': 'world'},
14                {'queue_size':100}
15            ],
16            remappings=[
17                ('cloud_in','camera/camera/depth/color/points')
18            ],
19        ),
20    ])
21
```

Bezugspunkt der Octomap

Camera-Topic, welches die Pointcloud published

- Camera mit Parametern starten:

```
[INFO] [realsense2_camera_node-1]: process has finished cleanly [pid 20579]
emr@roboLab03:~/ur3_ws$ ros2 launch realsense2_camera rs_launch.py align_depth:=true pointcloud.enable:=true
```

- Broadcasts starten:

```
ros2 run emr2 tf_broadcaster camera_link -0.7 1 1.2 3 1.6 0
```

- Octomap-Server starten:

```
/src/emr2/launch$ ros2 launch emr2 octomap_server.launch.py
log files can be found below /home/emr/.ros/log/2024-06-19-12-01-26-715647-
```

- In RVIZ : Add → OccupancyGrid

Topic : /octomap-full

