

Follow Color VII

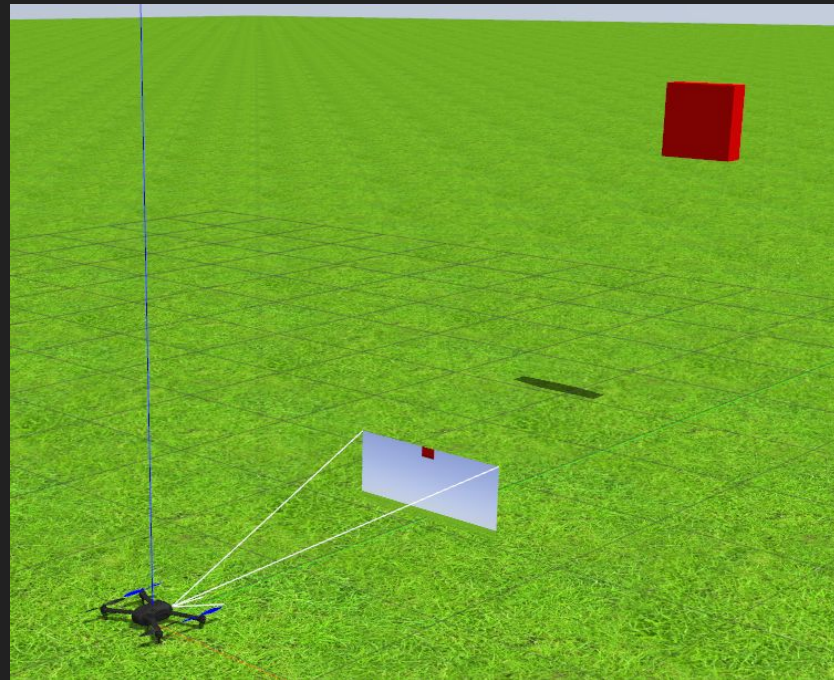
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Teleop Follow Color

1. Mismo paquete FollowColor
2. Nuevos launch, world
3. Nuevo modelo sin plugin
4. Nodo ROS para teleoperar el modelo
 - Servicios:

“gazebo/get_model_state”

“gazebo/set_model_state”



```
# Set Gazebo Model pose and twist
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
```

Teleop Target

w/x: increase/decrease linear Z velocity (~ 0.10)

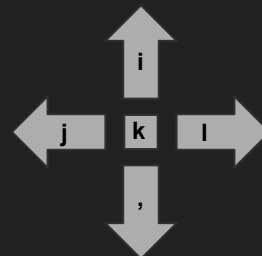
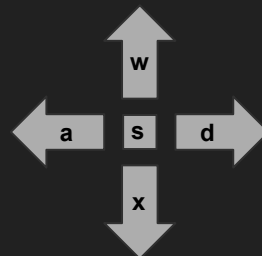
a/d: increase/decrease angular velocity (~ 0.1)

i/.: increase/decrease linear X velocity (~ 0.1)

j/l: increase/decrease linear Y velocity (~ 0.1)

space key, s, k: force stop

~~**00**: reset pose~~



Sim Follow Color

- Yaw:

$P=0.02$, $I=0$, $D=0.001$

- V_z :

$P=0.05$, $I=0$, $D=0.005$

- V_x :

$P=0.2$, $I=0$, $D=0.0002$



Otros cambios

- Error relativo \rightarrow No depende del tamaño de la imagen
- Trabajo de Investigación Tutelado