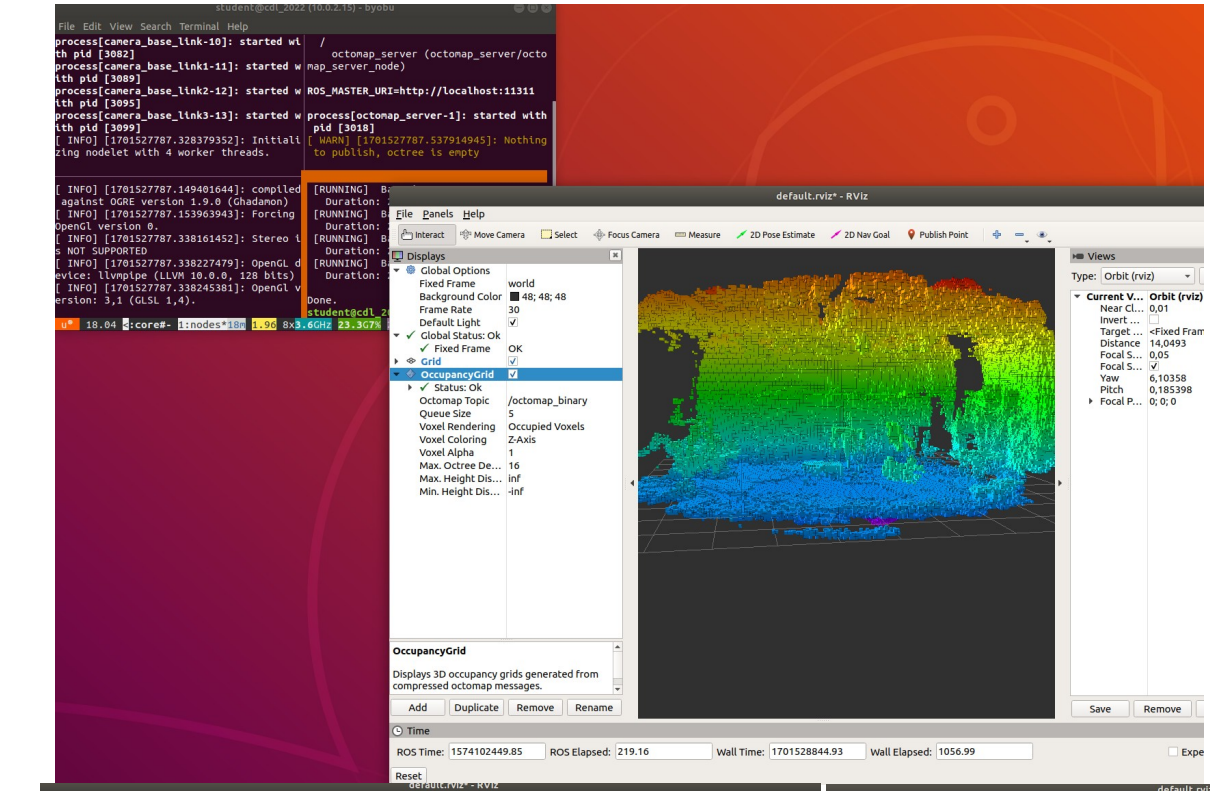
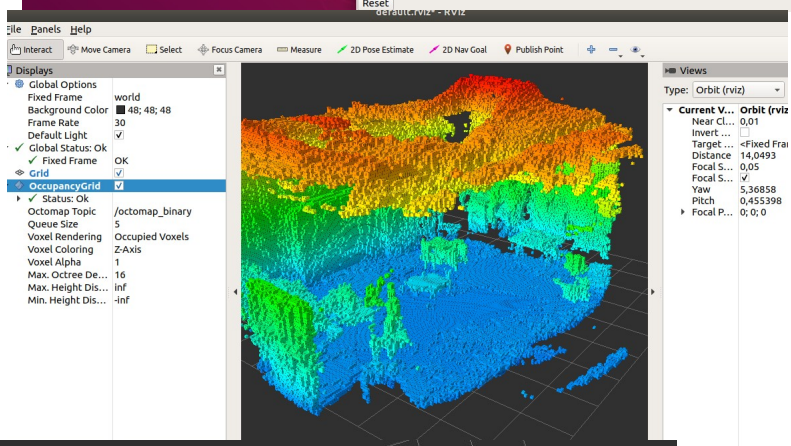
Assignment 1 - Report

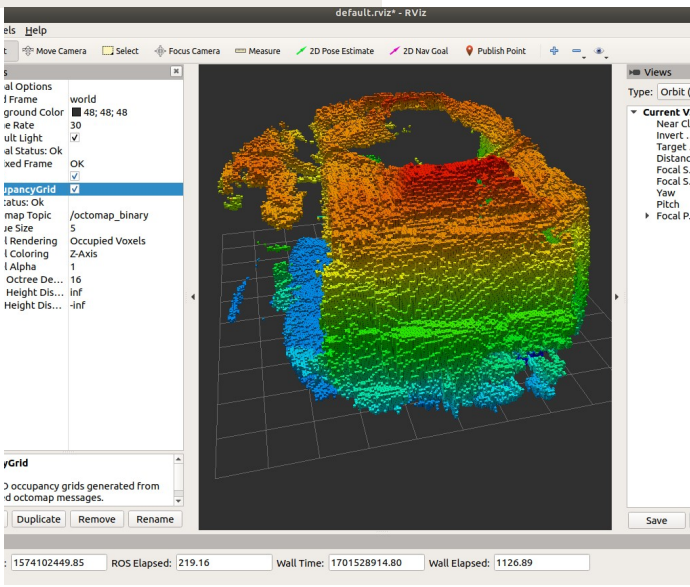
Gruppe 23 - Florian Werkl, Stefan Schörkmeier

Image(s) showing your obtained Octomap (similar to Fig. 1 above)

In the following images we can see the generated octomap and the byobu window which was created with a script:







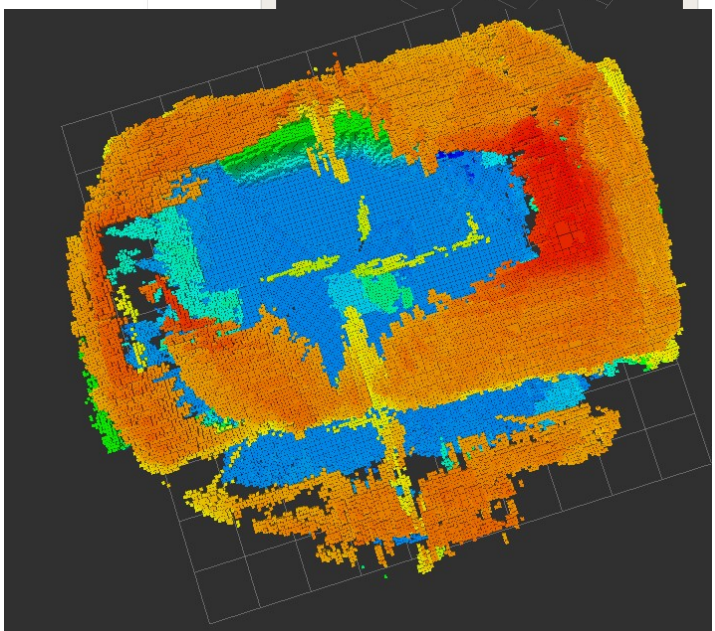
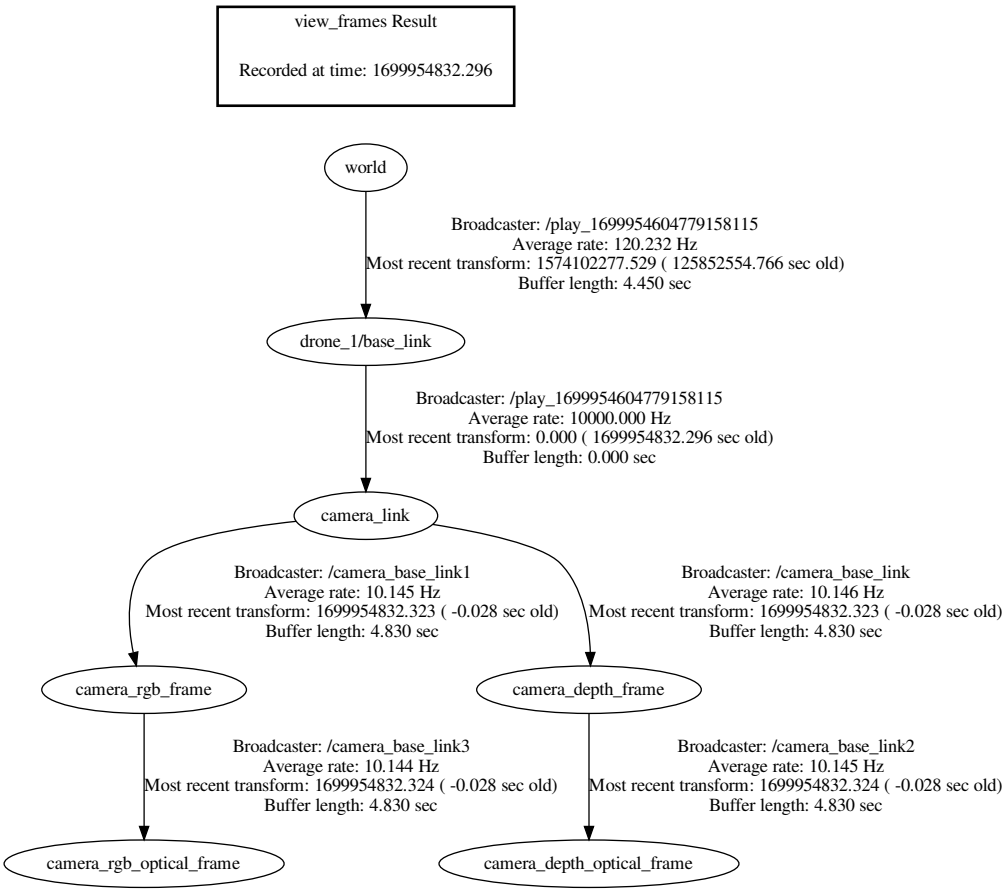
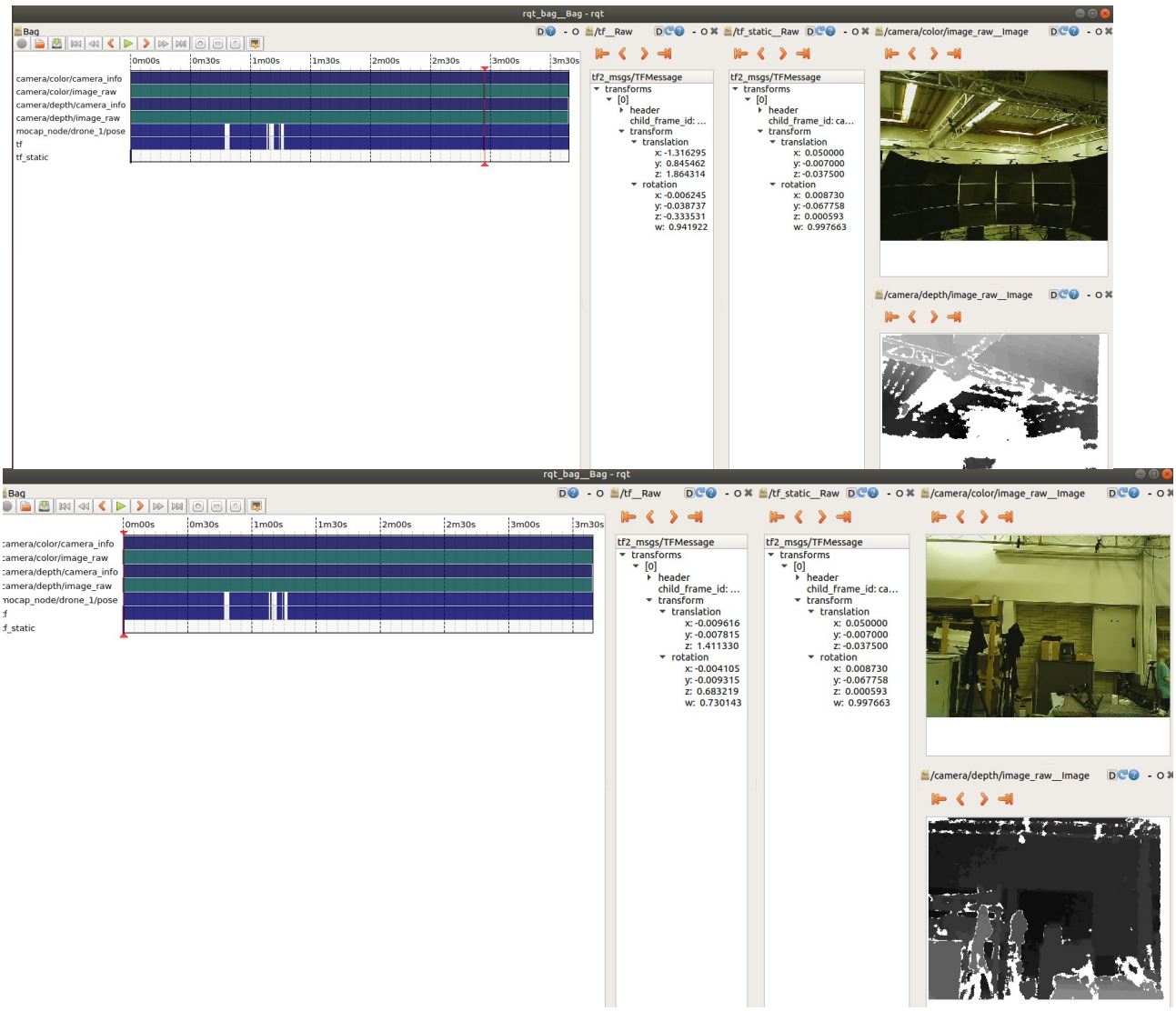


Image of perfect tf-tree (similar to Fig. 2 above)
In the next image we see the tf-tree, which tells us the transform positions of different nodes:



Rosbag inspection (e.g., using rqt-bag or rosbag info in the terminal).
In the following images we did the inspection of the rosbag:




```
student@cdl_2022:~/camera-drones$ rosbag info assignment_1/2019-11-18-19-37-10.bag
path:        assignment_1/2019-11-18-19-37-10.bag
version:     2.0
duration:    3:39s (219s)
start:       Nov 18 2019 19:37:10.68 (1574102230.68)
end:         Nov 18 2019 19:40:49.85 (1574102449.85)
size:        1.6 GB
messages:    53697
compression: none [1102/1102 chunks]
types:       geometry_msgs/PoseStamped [d3812c3cbc69362b77dc0b19b345f8f5]
             sensor_msgs/CameraInfo    [c9a58c1b0b154e0e6da7578cb991d214]
             sensor_msgs/Image         [060021388200f6f0f447d0fcd9c64743]
             tf2_msgs/TFMessage        [94810edda583a504dfda3829e70d7eec]
topics:      /camera/color/camera_info    1096 msgs    : sensor_msgs/CameraInfo
             /camera/color/image_raw      1096 msgs    : sensor_msgs/Image
             /camera/depth/camera_info    1075 msgs    : sensor_msgs/CameraInfo
             /camera/depth/image_raw      1075 msgs    : sensor_msgs/Image
             /mocap_node/drone_1/pose    24675 msgs    : geometry_msgs/PoseStamped
             /tf                         24675 msgs    : tf2_msgs/TFMessage
             /tf_static                      5 msgs    : tf2_msgs/TFMessage        (5 connections)
student@cdl_2022:~/camera-drones$
```

Here we played around with the topics to really understand the data which we were given. Through that it was quiet easy to solve assignment 1, after we have understood what parts were important for this assignment.

Appendix:
A short picture of the first time using RVIZ and playing around with it.