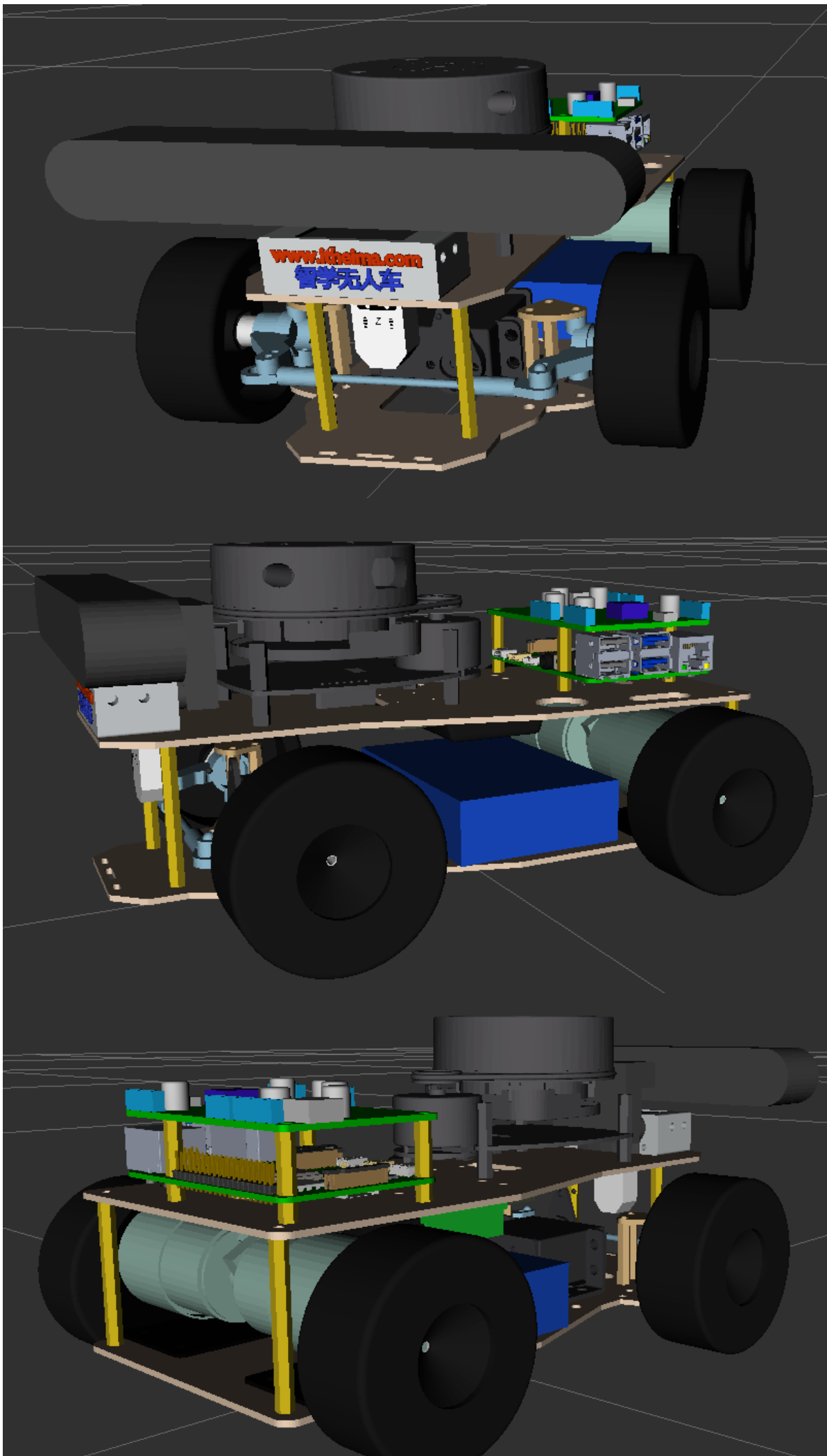
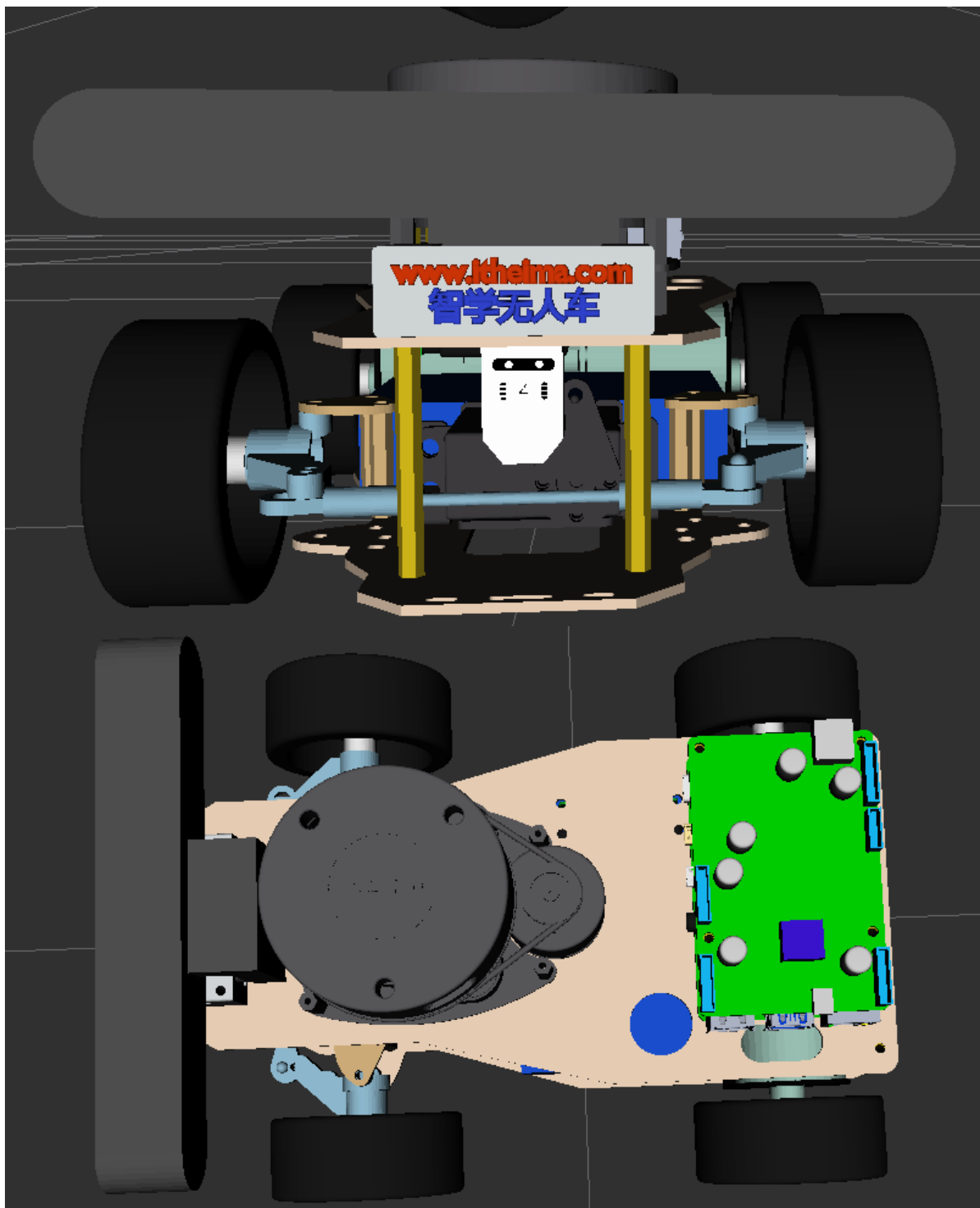


效果显示





urdf模型

```

1  <?xml version="1.0"?>
2  <robot name="car" xmlns:xacro="http://www.ros.org/wiki/xacro">
3
4      <xacro:property name="wheel_base" value="0.162"/>
5      <xacro:property name="ground_clearance" value="0.019"/>
6      <xacro:property name="front_offset" value="0.074"/>
7      <xacro:property name="back_offset" value="0.069"/>
8
9      <xacro:property name="pkg" value="zxcar_description" />
10
11     <xacro:macro name="HMCARBody" params="name">
12         <link name="${name}">
13             <visual>

```

```

14         <geometry>
15             <mesh
filename="package://${pkg}/meshes/ackerman_body.dae"/>
16         </geometry>
17         <origin xyz="0 0 0" rpy="0 0 0"/>
18     </visual>
19 </link>~~~~
20 </xacro:macro>
21
22     <xacro:macro name="HMCARwheel" params="name left='true' xyz='0 0 0'
rpy='0 0 0'">
23         <link name="${name}">
24             <visual>
25                 <geometry>
26                     <xacro:if value="${left}">
27                         <mesh
filename="package://${pkg}/meshes/wheel_left.dae"/>
28                     </xacro:if>
29                     <xacro:unless value="${left}">
30                         <mesh
filename="package://${pkg}/meshes/wheel_right.dae"/>
31                     </xacro:unless>
32                 </geometry>
33                 <origin xyz="${xyz}" rpy="${rpy}"/>
34             </visual>
35         </link>
36     </xacro:macro>
37
38     <xacro:macro name="HMwheelJoint" params="name parent child
type='continuous' xyz='0 0 0' rpy='0 0 0' axis='0 1 0'">
39         <joint name="${name}" type="${type}">
40             <parent link="${parent}"/>
41             <child link="${child}"/>
42             <origin xyz="${xyz}" rpy="${rpy}"/>
43             <axis xyz="${axis}"/>
44         </joint>
45     </xacro:macro>
46
47     <xacro:HMCARBody name="base_link"/>
48
49     <xacro:HMCARwheel name="front_left"/>
50
51     <xacro:HMwheelJoint
52         name="joint_front_left"
53         parent="base_link"
54         child="front_left"
55         xyz="${front_offset} ${wheel_base/2} 0.019"/>
56
57     <xacro:HMCARwheel name="front_right" left="false"/>
58
59     <xacro:HMwheelJoint
60         name="joint_front_right"
61         parent="base_link"
62         child="front_right"
63         xyz="${front_offset} -${wheel_base/2} ${ground_clearance}"/>
64
65     <xacro:HMCARwheel name="back_left"/>
66

```

```
67     <xacro:HMwheelJoint
68         name="joint_back_left"
69         parent="base_link"
70         child="back_left"
71         xyz="-${back_offset} ${wheel_base/2} ${ground_clearance}"/>
72
73     <xacro:HMCarWheel name="back_right" left="false"/>
74
75     <xacro:HMwheelJoint
76         name="joint_back_right"
77         parent="base_link"
78         child="back_right"
79         xyz="-${back_offset} -${wheel_base/2} ${ground_clearance}"/>
80
81 </robot>
```