	dist finder.py Source Code
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	function get Range (data, Heta):
_	$\theta_i = \theta_s + i\theta_\Delta$
	where $\theta$ is the angle at Scan point i
	to is the angle-min variable in ROS Laxerscanins
	As is the angle-increment variable in Ros LaserScan.msg
	to find index of point at 50°:
	$\theta_i \rightarrow 50^{\circ}$
<u>}                                    </u>	$\frac{50 = \theta_0 + i\theta_0}{ i = 50 - \theta_0 }$
	$i = 50 - \theta_0$
	$\theta_{\lambda}$
	Connecting LIDAR to windows with UrgBenri
	go to retwork seffings for USB-ethernet adapter.
	goto TCP/1PV4
	- set ip addres: 192.168.1.15
	subnet mark: 255, 255, 255, 0
	defulf gateway: 192.168.1.1
·	*Also dissonment from wifi
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. Marie de la constante de la	Connecting to LIDAR on Jetson
	Make sure to Select Hokuyo Connection in Networks
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	run (ommand: 1 = rosrun urg-node urg-node _ip_address:= "192.168:1.11"
	You can display the Sensor data by running:= restopic echo pen
	Compiling Teensy firmware
	In any folder start clean:
et mens a keen stret fit bred na han na filosof ee I het fit a d'heer bena ee en dess et baseen a v	1. mkdir catkin-wr
Statement for Statement and addition (published)	2. Cd catkin-ws
''l derfe-bandlard fella us ma a' a' encorr	3. mkdir src
	4. cd src
	5. catkin_init_workspace
	6. git clone https://github.com/ror-drivers/rosscrin/.git
	7. Cd. rosserial and git checkout indigo-devel
	8. In a completely reperate folder outside this
1	Catkin project do
	git Clone https://github.com/nischalkn/Fltenth.gi7
	9. copy the folder race in Fltenth_master/arc_ws/src/ra
	to Catkin_Ws/src/rosserial
	10. edit the file CMakeLists, txt in catkin-us/sre/
	rosserial/rosserial_andvino/cmake Lists.txt

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