View point cloud data

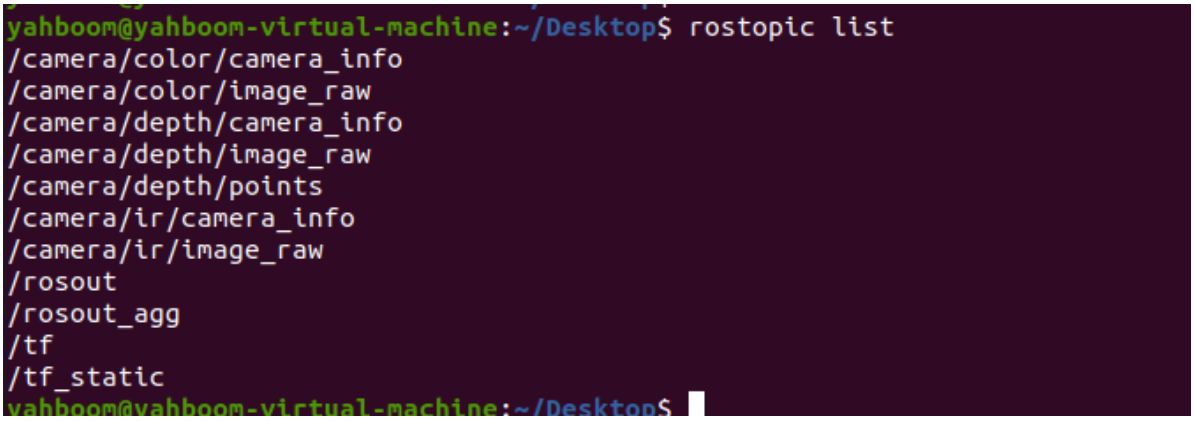
1. Viewing deep point clouds

Input following command:

```
roslaunch orbbec_camera orbbec_camera.launch
```

View topic data:

```
rostopic list
```



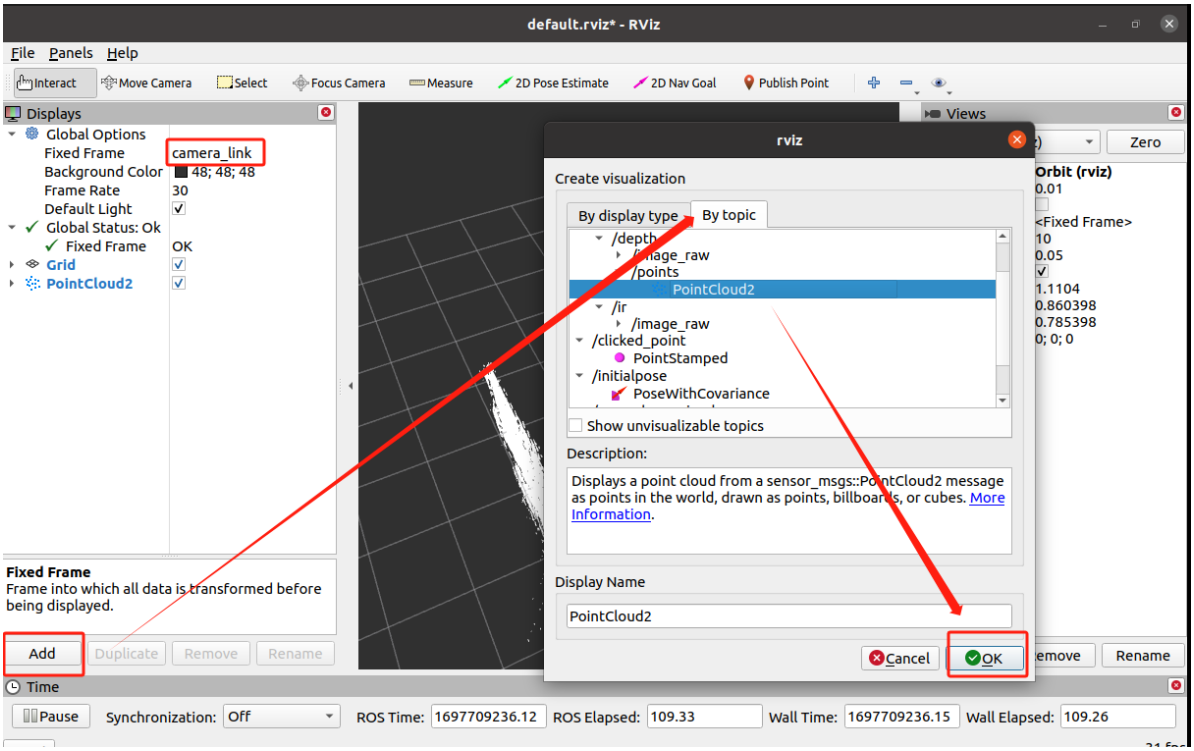
As shown in the above figure, the topic name for deep point clouds is:/camera/depth/points.

Open rviz to view the point cloud.

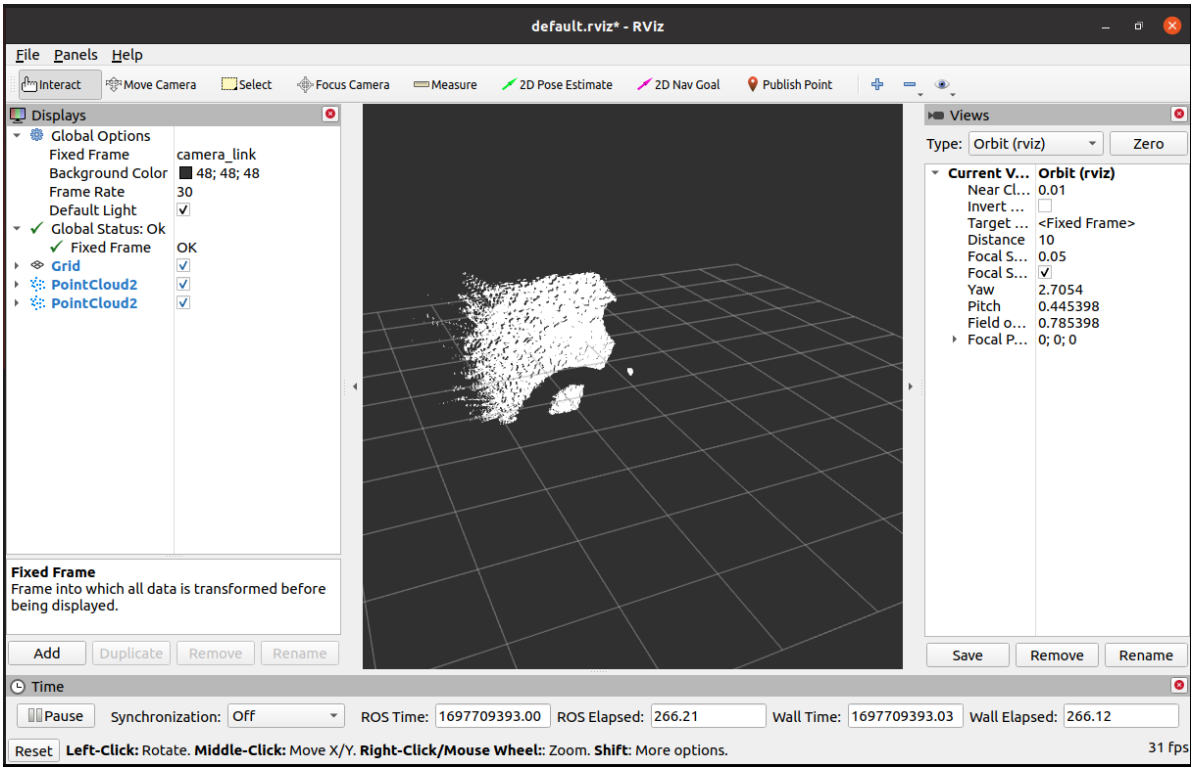
```
rviz
```

After opening it, set it as shown in the following figure and change the Fixed Frame under Global Options to camera_ Link, and then click [Add].

Select [By topic], select **/depth/points/PointCloud2**, and click [OK] to complete the settings.



The point cloud displayed is as follows:



2. Viewing color point clouds

Input following command to start camera:

```
roslaunch orbbec_camera orbbec_camera.launch
```

View topics:

```
rostopic list
```

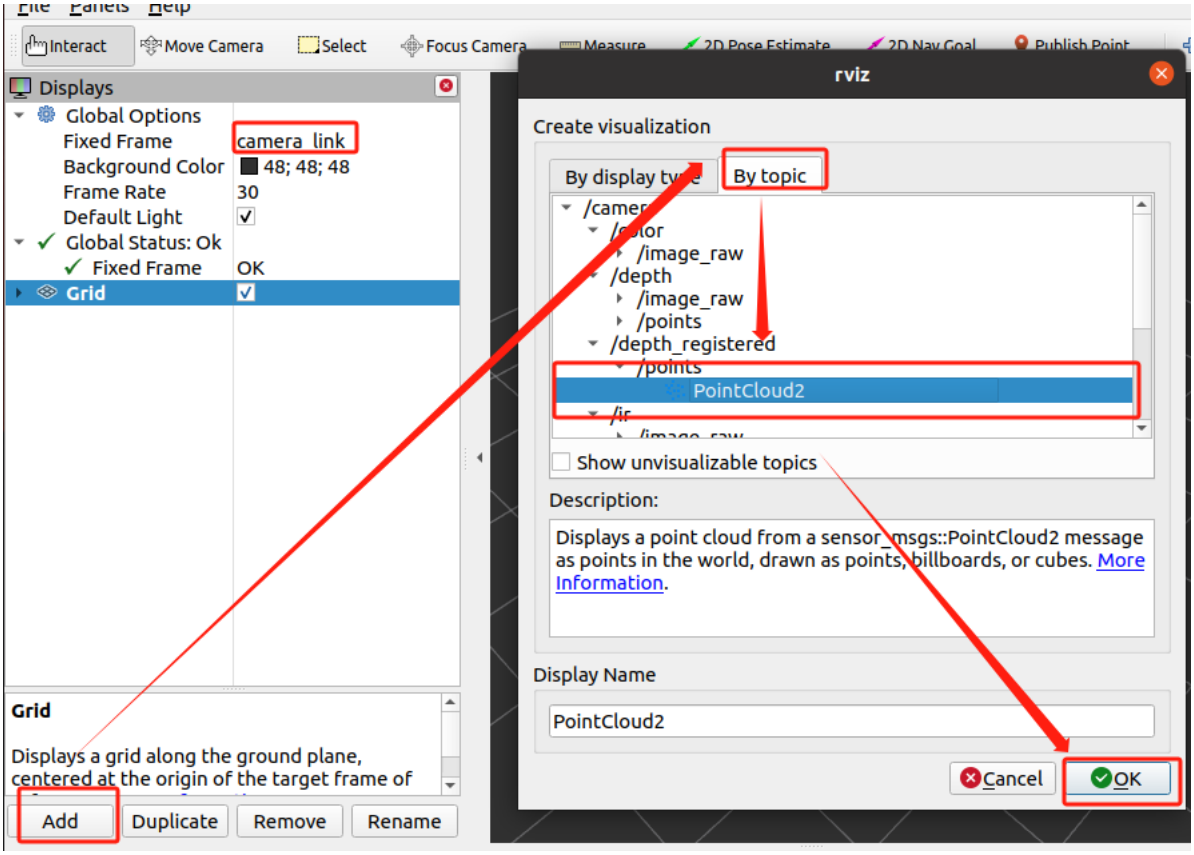
```
yahboom@yahboom-virtual-machine:~/Desktop$ rostopic list
/camera/color/camera_info
/camera/color/image_raw
/camera/depth/camera_info
/camera/depth/image_raw
/camera/depth/points
/camera/depth_registered/points
/camera/ir/camera_info
/camera/ir/image_raw
/clicked_point
/initialpose
/move_base_simple/goal
/rosout
/rosout_agg
/tf
/tf_static
```

The topic of color point clouds is/camera/depth_ Registered/points, open rviz to view.

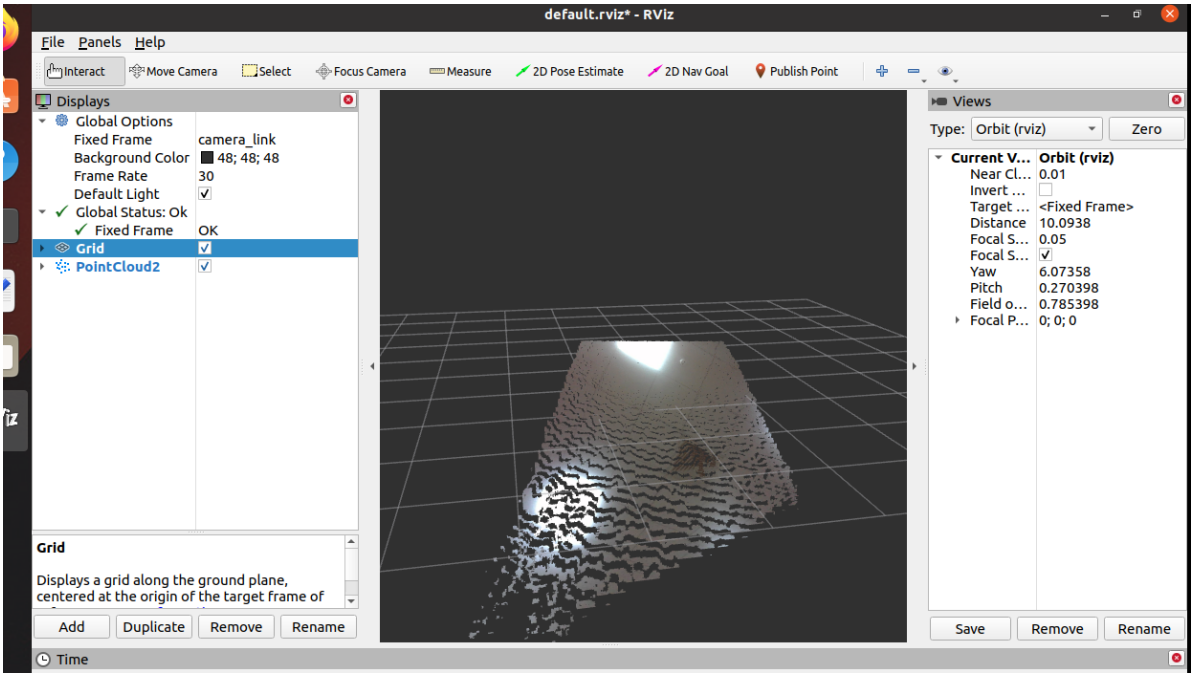
```
rviz
```

After opening it, set it as shown in the following figure and change the Fixed Frame under Global Options to camera_ Link, and then click [Add].

Select [By topic], select **/camera/depth_registered/points/PointCloud2**, and click [OK] to complete the settings.



The displayed color point cloud is as follows:


default.rviz* - RViz
File Panels Help
Interact
Move Camera
Select
Focus Camera
Measure
2D Pose Estimate
2D Nav Goal
Publish Point
Displays
Global Options
Fixed Frame camera_link
Background Color 48; 48; 48
Frame Rate 30
Default Light
Global Status: Ok
Fixed Frame OK
Grid
PointCloud2
Grid
Displays a grid along the ground plane, centered at the origin of the target frame of
Add
Duplicate
Remove
Rename
Views
Type: Orbit (rviz)
Zero
Current V... Orbit (rviz)
Near Cl... 0.01
Invert ...
Target ... <Fixed Frame>
Distance 10.0938
Focal S... 0.05
Focal S...
Yaw 6.07358
Pitch 0.270398
Field o... 0.785398
Focal P... 0; 0; 0
Save
Remove
Rename
Time