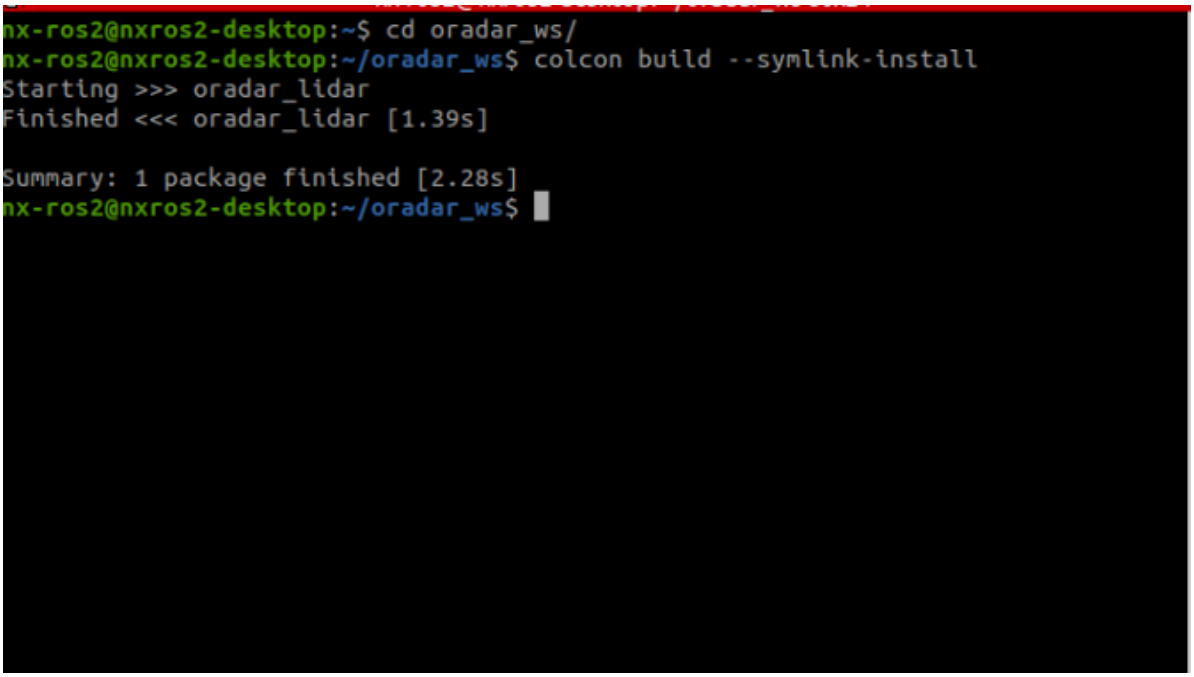
Use lidar in ROS2

1、Compile function package

Extract oradar_ lidar_ Oradar from ros2.zip_ Lidar, put oradar_ Lidar is copied to the src directory of the created workspace, where the workspace name is oradar_ Ws as an example, oradar_ The path of ws is in the~directory, and then returns to the workspace directory.

Input following command to complie.

```
cd ~/oradar_ws
colcon  build --symlink-install
```



The above picture shows that the compilation has passed.

Then enter the following command to set the environment variable.

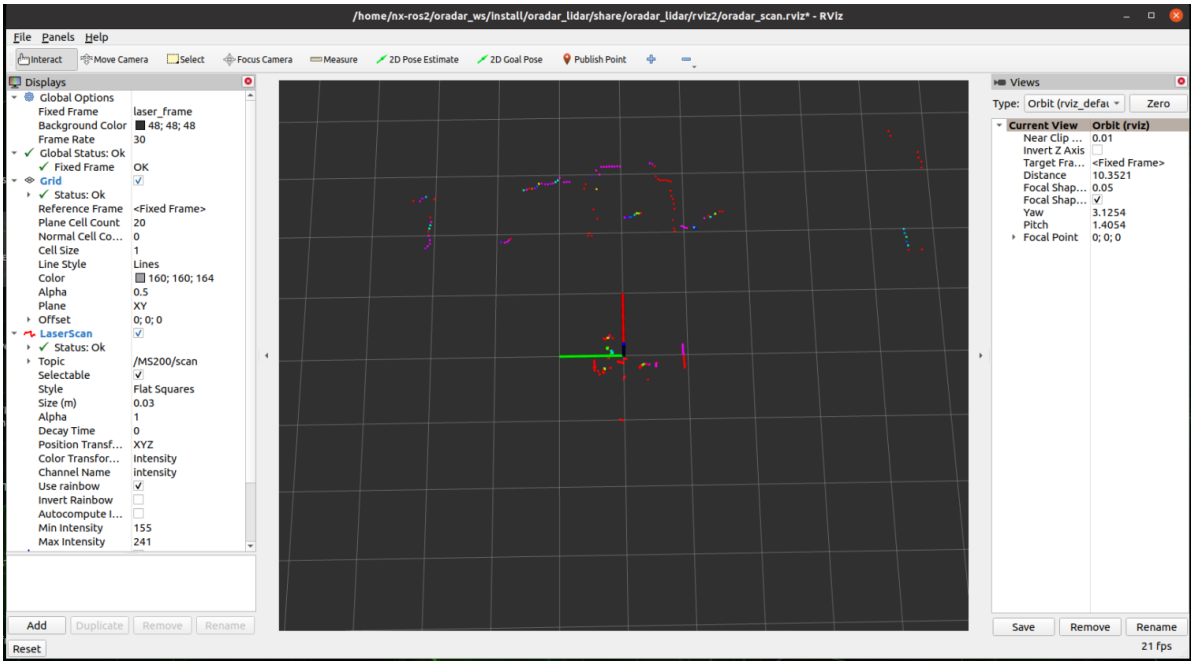
```
source install/setup.bash
```

2、Run launch

Before operation, you need to refer to the first section and bind the following radar port names.

For details, refer to the section "1. Preparation before use - Bind radar port names". After binding the radar, enter the following command to start the lidar.

```
ros2 launch oradar_lidar ms200_scan_view.launch.py
```



You can view lidar node data through the following command.

```
ros2 topic echo
```

```
header:
  stamp:
    sec: 1677134404
    nanosec: 903166855
  frame_id: laser_frame
angle_min: 0.013962420634925365
angle_max: 6.269222736358643
angle_increment: 0.014025247655808926
time_increment: 0.0002240974281448871
scan_time: 0.09994745254516602
range_min: 0.05000000074505806
range_max: 20.0
ranges:
- 1.9500000476837158
- 2.239000082015991
- 2.236999988555908
- 2.242000102996826
- 2.2239999771118164
- 2.2139999866485596
- 2.2219998836517334
- 2.234999895095825
- 2.24399995803833
- 2.249000072479248
- 2.255000114440918
- 2.2720000743865967
- 2.3210000991821289
- 2.2200000286102295
- 0.0
- 0.0
- 2.312000036239624
- 2.1640000343322754
- 2.0269999504089355
- 2.0280001163482666
- 3.005000114440918
- 3.0179998874664307
- 3.0299999713897705
- 3.1740000247955322
- 3.062000036239624
- 3.068000078201294
- 3.07100009918213
- 3.0820000171661377
- 3.0899999141693115
- 3.118000030517578
- 3.226000070571899
```