

Gazebo Sim (Harmonic) Plugins and Sensors for ROS2

6 min read · Oct 11, 2024



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You can access code examples from [this GitHub repository](#). The repository includes a variety of sensor applications for simulation. I'm thinking about adding content on how to use GazeboSim sensor data with ROS2 and RViz2. If you're interested in integrating with ROS2, let me know with a like or comment. Stay tuned, and happy reading!



Gazebo Sim Harmonic

Sensors

GPU Lidar

```
<sensor name="gpu_lidar" type="gpu_lidar">
  <lidar>
    <scan>
      <horizontal>
        <samples>1800</samples>
        <resolution>1</resolution>
        <min_angle>-3.1459</min_angle>
        <max_angle>3.1459</max_angle>
      </horizontal>
      <vertical>
        <samples>16</samples>
        <resolution>1</resolution>
        <min_angle>-0.261799</min_angle>
        <max_angle>0.261799</max_angle>
      </vertical>
    </scan>
    <range>
      <min>0.05</min>
      <max>100</max>
      <resolution>0.01</resolution>
    </range>
    <noise>
      <type>gaussian</type>
      <mean>0</mean>
      <stddev>0.01</stddev>
    </noise>
  </lidar>
  <gz_frame_id>saye/sensor_link</gz_frame_id>
  <topic>laser_scan</topic>
  <visualize>true</visualize>
  <update_rate>10</update_rate>
</sensor>
```

IMU

```
<!-- IMU -->
<sensor name="imu_sensor" type="imu">
  <always_on>1</always_on>
  <update_rate>50</update_rate>
  <imu>
    <enable_orientation>0</enable_orientation>
    <angular_velocity>
      <x>
        <noise type="gaussian">
```

```

        <mean>0</mean>
        <stddev>0.009</stddev>
        <bias_mean>0.00075</bias_mean>
        <bias_stddev>0.005</bias_stddev>
        <dynamic_bias_stddev>0.00002</dynamic_bias_stddev>
        <dynamic_bias_correlation_time>400.0</dynamic_bias_correlation_time>
        <precision>0.00025</precision>
    </noise>
</x>
<y>
    <noise type="gaussian">
        <mean>0</mean>
        <stddev>0.009</stddev>
        <bias_mean>0.00075</bias_mean>
        <bias_stddev>0.005</bias_stddev>
        <dynamic_bias_stddev>0.00002</dynamic_bias_stddev>
        <dynamic_bias_correlation_time>400.0</dynamic_bias_correlation_time>
        <precision>0.00025</precision>
    </noise>
</y>
<z>
    <noise type="gaussian">
        <mean>0</mean>
        <stddev>0.009</stddev>
        <bias_mean>0.00075</bias_mean>
        <bias_stddev>0.005</bias_stddev>
        <dynamic_bias_stddev>0.00002</dynamic_bias_stddev>
        <dynamic_bias_correlation_time>400.0</dynamic_bias_correlation_time>
        <precision>0.00025</precision>
    </noise>
</z>
</angular_velocity>
<linear_acceleration>
    <x>
        <noise type="gaussian">
            <mean>0</mean>
            <stddev>0.021</stddev>
            <bias_mean>0.05</bias_mean>
            <bias_stddev>0.0075</bias_stddev>
            <dynamic_bias_stddev>0.000375</dynamic_bias_stddev>
            <dynamic_bias_correlation_time>175.0</dynamic_bias_correlation_time>
            <precision>0.005</precision>
        </noise>
    </x>
    <y>
        <noise type="gaussian">
            <mean>0</mean>
            <stddev>0.021</stddev>
            <bias_mean>0.05</bias_mean>
            <bias_stddev>0.0075</bias_stddev>
            <dynamic_bias_stddev>0.000375</dynamic_bias_stddev>
            <dynamic_bias_correlation_time>175.0</dynamic_bias_correlation_time>
            <precision>0.005</precision>
        </noise>
    </y>
    <z>
        <noise type="gaussian">
            <mean>0</mean>
            <stddev>0.021</stddev>
            <bias_mean>0.05</bias_mean>
            <bias_stddev>0.0075</bias_stddev>
            <dynamic_bias_stddev>0.000375</dynamic_bias_stddev>
            <dynamic_bias_correlation_time>175.0</dynamic_bias_correlation_time>
            <precision>0.005</precision>
        </noise>
    </z>
</linear_acceleration>

```

```

        </noise>
    </y>
    <z>
        <noise type="gaussian">
            <mean>0</mean>
            <stddev>0.021</stddev>
            <bias_mean>0.05</bias_mean>
            <bias_stddev>0.0075</bias_stddev>
            <dynamic_bias_stddev>0.000375</dynamic_bias_stddev>
            <dynamic_bias_correlation_time>175.0</dynamic_bias_correlation_time>
            <precision>0.005</precision>
        </noise>
    </z>
</linear_acceleration>
</imu>
</sensor>

```

Intel Real Sense D435 RGBD Camera

```

<!-- Based on Intel realsense D435 (intrinsics and distortion not modeled) -->
<sensor name="rs_front" type="rgbd_camera">
    <pose>0.122 0 0.257 0 0.46 0</pose>
    <always_on>1</always_on>
    <update_rate>30</update_rate>
    <camera name="rs_front">
        <horizontal_fov>1.50098</horizontal_fov>
        <lens>
            <intrinsics>
                <!-- fx = fy = width / ( 2 * tan (hfov / 2 ) ) -->
                <fx>343.159</fx>
                <fy>343.159</fy>
                <!-- cx = ( width - 1 ) / 2 -->
                <cx>319.5</cx>
                <!-- cy = ( height - 1 ) / 2 -->
                <cy>179.5</cy>
                <s>0</s>
            </intrinsics>
        </lens>
        <distortion>
            <k1>0.0</k1>
            <k2>0.0</k2>
            <k3>0.0</k3>
            <p1>0.0</p1>
            <p2>0.0</p2>
            <center>0.5 0.5</center>
        </distortion>
        <image>
            <width>640</width>

```

```

    <height>360</height>
    <format>R8G8B8</format>
  </image>
  <clip>
    <near>0.01</near>
    <far>300</far>
  </clip>
  <depth_camera>
    <clip>
      <near>0.1</near>
      <far>10</far>
    </clip>
  </depth_camera>
  <noise>
    <type>gaussian</type>
    <mean>0</mean>
    <stddev>0.007</stddev>
  </noise>
</camera>
</sensor>

```

Front Camera

```

<sensor name="camera_front" type="camera">
  <pose>0.111 0.03 0.235 0 0 0</pose>
  <always_on>1</always_on>
  <update_rate>25</update_rate>
  <camera name="camera_front">
    <horizontal_fov>1.658</horizontal_fov>
    <lens>
      <intrinsics>
        <!-- fx = fy = width / ( 2 * tan (hfov / 2 ) ) -->
        <fx>329.9</fx>
        <fy>329.9</fy>
        <!-- cx = ( width - 1 ) / 2 -->
        <cx>359.5</cx>
        <!-- cy = ( height - 1 ) / 2 -->
        <cy>539.5</cy>
        <s>0</s>
      </intrinsics>
    </lens>
    <distortion>
      <k1>0.0</k1>
      <k2>0.0</k2>
      <k3>0.0</k3>
      <p1>0.0</p1>
      <p2>0.0</p2>
      <center>0.5 0.5</center>
    </distortion>
  </camera>
</sensor>

```

```

    </distortion>
    <image>
      <width>720</width>
      <height>1080</height>
      <format>R8G8B8</format>
    </image>
    <clip>
      <near>0.01</near>
      <far>300</far>
    </clip>
    <noise>
      <type>gaussian</type>
      <mean>0</mean>
      <stddev>0.007</stddev>
    </noise>
  </camera>
</sensor>

```

Rear Camera

```

<sensor name="camera_rear" type="camera">
  <pose>0.069 -0.03 0.235 0 0 3.141592653589793</pose>
  <always_on>1</always_on>
  <update_rate>25</update_rate>
  <camera name="camera_rear">
    <horizontal_fov>1.658</horizontal_fov>
    <lens>
      <intrinsics>
        <!-- fx = fy = width / ( 2 * tan (hfov / 2 ) ) -->
        <fx>329.9</fx>
        <fy>329.9</fy>
        <!-- cx = ( width - 1 ) / 2 -->
        <cx>359.5</cx>
        <!-- cy = ( height - 1 ) / 2 -->
        <cy>539.5</cy>
        <s>0</s>
      </intrinsics>
    </lens>
    <distortion>
      <k1>0.0</k1>
      <k2>0.0</k2>
      <k3>0.0</k3>
      <p1>0.0</p1>
      <p2>0.0</p2>
      <center>0.5 0.5</center>
    </distortion>
    <image>
      <width>720</width>

```

```

    <height>1080</height>
    <format>R8G8B8</format>
  </image>
  <clip>
    <near>0.01</near>
    <far>300</far>
  </clip>
  <noise>
    <type>gaussian</type>
    <mean>0</mean>
    <stddev>0.007</stddev>
  </noise>
</camera>
</sensor>

```

Camera Left

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```

<sensor name="camera_left" type="camera">
  <pose>0.085 0.09 0.27 0 0 1.5707963267948966</pose>
  <always_on>1</always_on>
  <update_rate>25</update_rate>
  <camera name="camera_left">
    <horizontal_fov>1.658</horizontal_fov>
    <lens>
      <intrinsics>
        <!-- fx = fy = width / ( 2 * tan (hfov / 2 ) ) -->
        <fx>329.9</fx>
        <fy>329.9</fy>
        <!-- cx = ( width - 1 ) / 2 -->
        <cx>359.5</cx>
        <!-- cy = ( height - 1 ) / 2 -->
        <cy>539.5</cy>
        <s>0</s>
      </intrinsics>
    </lens>
  </camera>
</sensor>

```

```

    <distortion>
      <k1>0.0</k1>
      <k2>0.0</k2>
      <k3>0.0</k3>
      <p1>0.0</p1>
      <p2>0.0</p2>
      <center>0.5 0.5</center>
    </distortion>
    <image>
      <width>720</width>
      <height>1080</height>
      <format>R8G8B8</format>
    </image>
    <clip>
      <near>0.01</near>
      <far>300</far>
    </clip>
    <noise>
      <type>gaussian</type>
      <mean>0</mean>
      <stddev>0.007</stddev>
    </noise>
  </camera>
</sensor>

```

Camera Right

```

<sensor name="camera_right" type="camera">
  <pose>0.085 -0.09 0.27 0 0 -1.5707963267948966</pose>
  <always_on>1</always_on>
  <update_rate>25</update_rate>
  <camera name="camera_right">
    <horizontal_fov>1.658</horizontal_fov>
    <lens>
      <intrinsics>
        <!-- fx = fy = width / ( 2 * tan (hfov / 2 ) ) -->
        <fx>329.9</fx>
        <fy>329.9</fy>
        <!-- cx = ( width - 1 ) / 2 -->
        <cx>359.5</cx>
        <!-- cy = ( height - 1 ) / 2 -->
        <cy>539.5</cy>
        <s>0</s>
      </intrinsics>
    </lens>
    <distortion>
      <k1>0.0</k1>
      <k2>0.0</k2>

```



```

        <k3>0.0</k3>
        <p1>0.0</p1>
        <p2>0.0</p2>
        <center>0.5 0.5</center>
    </distortion>
    <image>
        <width>720</width>
        <height>1080</height>
        <format>R8G8B8</format>
    </image>
    <clip>
        <near>0.01</near>
        <far>300</far>
    </clip>
    <noise>
        <type>gaussian</type>
        <mean>0</mean>
        <stddev>0.007</stddev>
    </noise>
</camera>
</sensor>

```

Magnetometer

```

<sensor name="magnetometer" type="magnetometer">
  <always_on>1</always_on>
  <update_rate>50</update_rate>
  <magnetometer>
    <x>
      <noise type="gaussian">
        <mean>0.000000080</mean>
        <bias_mean>0.000000400</bias_mean>
      </noise>
    </x>
    <y>
      <noise type="gaussian">
        <mean>0.000000080</mean>
        <bias_mean>0.000000400</bias_mean>
      </noise>
    </y>
    <z>
      <noise type="gaussian">
        <mean>0.000000080</mean>
        <bias_mean>0.000000400</bias_mean>
      </noise>
    </z>
  </magnetometer>
</sensor>

```

```
</magnetometer>  
</sensor>
```

Thermal Camera

```
<sensor name="thermal_camera" type="thermal">  
  <pose>0.44 -0.17 0.574 0 0 0</pose>  
  <camera name="thermal_camera">  
    <horizontal_fov>0.628</horizontal_fov>  
    <lens>  
      <intrinsics>  
        <!-- fx = fy = width / ( 2 * tan (hfov / 2 ) ) -->  
        <fx>317.173</fx>  
        <fy>317.173</fy>  
        <!-- cx = ( width - 1 ) / 2 -->  
        <cx>102.5</cx>  
        <!-- cy = ( height - 1 ) / 2 -->  
        <cy>77.5</cy>  
        <s>0</s>  
      </intrinsics>  
    </lens>  
    <image>  
      <width>206</width>  
      <height>156</height>  
      <format>L8</format>  
    </image>  
    <clip>  
      <near>0.1</near>  
      <far>100</far>  
    </clip>  
  </camera>  
  <always_on>1</always_on>  
  <update_rate>9</update_rate>  
  <plugin  
    filename="gz-sim-thermal-sensor-system"  
    name="gz::sim::systems::ThermalSensor">  
    <min_temp>253.15</min_temp>  
    <max_temp>673.15</max_temp>  
    <resolution>1.6</resolution>  
  </plugin>  
</sensor>
```

NavSat Sensor

```
<sensor name="navsat_sensor" type="navsat">
  <always_on>1</always_on>
  <update_rate>30</update_rate>
</sensor>
```

Air Pressure

```
<sensor name="air_pressure" type="air_pressure">
  <always_on>1</always_on>
  <update_rate>20</update_rate>
  <air_pressure>
    <reference_altitude>0</reference_altitude>
    <noise type="gaussian">
      <mean>0.000000008</mean>
    </noise>
  </air_pressure>
</sensor>
```

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Contact Sensor

```
<sensor name='sensor_contact' type='contact'>
  <contact>
    <collision>collision_sphere</collision>
    <topic>/contact_example</topic>
  </contact>
  <always_on>1</always_on>
  <update_rate>100</update_rate>
</sensor>
```

Plugins

```
<plugin
  filename="gz-sim-physics-system"
  name="gz::sim::systems::Physics">
```

```
</plugin>
<plugin
  filename="gz-sim-air-pressure-system"
  name="gz::sim::systems::AirPressure">
</plugin>
<plugin
  filename="gz-sim-altimeter-system"
  name="gz::sim::systems::Altimeter">
</plugin>
<plugin
  filename="gz-sim-imu-system"
  name="gz::sim::systems::Imu">
</plugin>
<plugin
  filename="gz-sim-magnetometer-system"
  name="gz::sim::systems::Magnetometer">
</plugin>
<plugin
  filename="gz-sim-forcetorque-system"
  name="gz::sim::systems::ForceTorque">
  <gz::system_priority>10</gz::system_priority>
</plugin>
<plugin
  filename="gz-sim-user-commands-system"
  name="gz::sim::systems::UserCommands">
</plugin>
<plugin
  filename="gz-sim-scene-broadcaster-system"
  name="gz::sim::systems::SceneBroadcaster">
</plugin>

<plugin
  filename="gz-sim-joint-controller-system"
  name="gz::sim::systems::JointController">
  <joint_name>j1</joint_name>
  <initial_velocity>1.0</initial_velocity>
</plugin>

<plugin
  filename="gz-sim-pose-publisher-system"
  name="gz::sim::systems::PosePublisher">
  <publish_link_pose>true</publish_link_pose>
  <use_pose_vector_msg>true</use_pose_vector_msg>
  <static_publisher>true</static_publisher>
  <static_update_frequency>1</static_update_frequency>
</plugin>

<plugin
  filename="gz-sim-odometry-publisher-system"
  name="gz::sim::systems::OdometryPublisher">
  <odom_frame>vehicle/odom</odom_frame>
  <robot_base_frame>vehicle</robot_base_frame>
</plugin>
```

```

<plugin
  filename="gz-sim-diff-drive-system"
  name="gz::sim::systems::DiffDrive">
  <left_joint>front_left_wheel_joint</left_joint>
  <left_joint>rear_left_wheel_joint</left_joint>
  <right_joint>front_right_wheel_joint</right_joint>
  <right_joint>rear_right_wheel_joint</right_joint>
  <wheel_separation>1.25</wheel_separation>
  <wheel_radius>0.3</wheel_radius>
  <topic>cmd_vel</topic>
</plugin>

<plugin filename="gz-sim-triggered-publisher-system"
  name="gz::sim::systems::TriggeredPublisher">
  <input type="gz.msgs.Empty" topic="/reset_robot"/>
  <output type="gz.msgs.Twist" topic="/cmd_vel">
    linear: {x: 0}
  </output>
  <service
    name="/world/triggered_publisher/set_pose"
    reqType="gz.msgs.Pose"
    repType="gz.msgs.Boolean"
    timeout="3000"
    reqMsg="name: 'blue_vehicle', id: 8, position: {x: -3, z: 1}">
  </service>
</plugin>

<world>
  ...
  <plugin filename="gz-sim-altimeter-system"
    name="gz::sim::systems::Altimeter">
  </plugin>
  ...
</world>

<plugin
  filename="gz-sim-diff-drive-system"
  name="gz::sim::systems::DiffDrive">
  <left_joint>left_wheel_joint</left_joint>
  <right_joint>right_wheel_joint</right_joint>
  <wheel_separation>1.25</wheel_separation>
  <wheel_radius>0.3</wheel_radius>
  <odom_publish_frequency>1</odom_publish_frequency>
  <max_linear_acceleration>1</max_linear_acceleration>
  <min_linear_acceleration>-1</min_linear_acceleration>
  <max_angular_acceleration>2</max_angular_acceleration>
  <min_angular_acceleration>-2</min_angular_acceleration>
  <max_linear_velocity>0.5</max_linear_velocity>
  <min_linear_velocity>-0.5</min_linear_velocity>
  <max_angular_velocity>1</max_angular_velocity>
  <min_angular_velocity>-1</min_angular_velocity>
</plugin>

```

```

<plugin
  filename="gz-sim-ackermann-steering-system"
  name="gz::sim::systems::AckermannSteering">
  <left_joint>front_left_wheel_joint</left_joint>
  <left_joint>rear_left_wheel_joint</left_joint>
  <right_joint>front_right_wheel_joint</right_joint>
  <right_joint>rear_right_wheel_joint</right_joint>
  <left_steering_joint>front_left_wheel_steering_joint</left_steering_joint>
  <right_steering_joint>front_right_wheel_steering_joint</right_steering_joint>
  <kingpin_width>1.0</kingpin_width>
  <steering_limit>0.5</steering_limit>
  <wheel_base>1.0</wheel_base>
  <wheel_separation>1.25</wheel_separation>
  <wheel_radius>0.3</wheel_radius>
  <min_velocity>-1</min_velocity>
  <max_velocity>1</max_velocity>
  <min_acceleration>-3</min_acceleration>
  <max_acceleration>3</max_acceleration>
</plugin>

<plugin
  filename="gz-sim-mecanum-drive-system"
  name="gz::sim::systems::MecanumDrive">
  <front_left_joint>front_left_wheel_joint</front_left_joint>
  <front_right_joint>front_right_wheel_joint</front_right_joint>
  <back_left_joint>rear_left_wheel_joint</back_left_joint>
  <back_right_joint>rear_right_wheel_joint</back_right_joint>
  <wheel_separation>1.25</wheel_separation>
  <wheelbase>1.511</wheelbase>
  <wheel_radius>0.3</wheel_radius>
  <min_acceleration>-5</min_acceleration>
  <max_acceleration>5</max_acceleration>
</plugin>

<plugin filename="ImageDisplay" name="Visible 2D">
  <topic>your_image_topic</topic>
  <gz-gui>
    <title>Visible 2D</title>
    <property key="state" type="string">docked</property>
    <property type="double" key="height">400</property>
    <property type="double" key="width">600</property>
  </gz-gui>
</plugin>

<gui fullscreen="0">

  <!-- 3D scene -->
  <plugin filename="MinimalScene" name="3D View">
    <gz-gui>
      <title>3D View</title>
      <property type="bool" key="showTitleBar">>false</property>
      <property type="string" key="state">docked</property>
    </gz-gui>
  </plugin>
</gui>

```

```

</gz-gui>

<engine>ogre2</engine>
<scene>scene</scene>
<ambient_light>1.0 1.0 1.0</ambient_light>
<background_color>0.8 0.8 0.8</background_color>
<camera_pose>-6 0 6 0 0.5 0</camera_pose>
</plugin>

<!-- Plugins that add functionality to the scene -->
<plugin filename="EntityContextMenuPlugin" name="Entity context menu">
  <gz-gui>
    <property key="state" type="string">floating</property>
    <property key="width" type="double">5</property>
    <property key="height" type="double">5</property>
    <property key="showTitleBar" type="bool">>false</property>
  </gz-gui>
</plugin>
<plugin filename="GzSceneManager" name="Scene Manager">
  <gz-gui>
    <property key="resizable" type="bool">>false</property>
    <property key="width" type="double">5</property>
    <property key="height" type="double">5</property>
    <property key="state" type="string">floating</property>
    <property key="showTitleBar" type="bool">>false</property>
  </gz-gui>
</plugin>
<plugin filename="InteractiveViewControl" name="Interactive view control">
  <gz-gui>
    <property key="resizable" type="bool">>false</property>
    <property key="width" type="double">5</property>
    <property key="height" type="double">5</property>
    <property key="state" type="string">floating</property>
    <property key="showTitleBar" type="bool">>false</property>
  </gz-gui>
</plugin>
<plugin filename="CameraTracking" name="Camera Tracking">
  <gz-gui>
    <property key="resizable" type="bool">>false</property>
    <property key="width" type="double">5</property>
    <property key="height" type="double">5</property>
    <property key="state" type="string">floating</property>
    <property key="showTitleBar" type="bool">>false</property>
  </gz-gui>
</plugin>

<!-- World control -->
<plugin filename="WorldControl" name="World control">
  <gz-gui>
    <title>World control</title>
    <property type="bool" key="showTitleBar">>false</property>
    <property type="bool" key="resizable">>false</property>
    <property type="double" key="height">72</property>

```

```

    <property type="double" key="z">1</property>

    <property type="string" key="state">floating</property>
    <anchors target="3D View">
      <line own="left" target="left"/>
      <line own="bottom" target="bottom"/>
    </anchors>
  </gz-gui>

  <play_pause>true</play_pause>
  <step>true</step>
  <start_paused>true</start_paused>
  <use_event>true</use_event>

</plugin>

<!-- World statistics -->
<plugin filename="WorldStats" name="World stats">
  <gz-gui>
    <title>World stats</title>
    <property type="bool" key="showTitleBar">false</property>
    <property type="bool" key="resizable">false</property>
    <property type="double" key="height">110</property>
    <property type="double" key="width">290</property>
    <property type="double" key="z">1</property>

    <property type="string" key="state">floating</property>
    <anchors target="3D View">
      <line own="right" target="right"/>
      <line own="bottom" target="bottom"/>
    </anchors>
  </gz-gui>

  <sim_time>true</sim_time>
  <real_time>true</real_time>
  <real_time_factor>true</real_time_factor>
  <iterations>true</iterations>
</plugin>

<plugin filename="ImageDisplay" name="Full 2D">
  <topic>topic_name</topic>
  <gz-gui>
    <title>Full 2D</title>
    <property key="state" type="string">docked</property>
    <property type="double" key="height">400</property>
    <property type="double" key="width">600</property>
  </gz-gui>
</plugin>

<plugin filename="ImageDisplay" name="Visible 2D">
  <topic>topic_name</topic>
  <gz-gui>
    <title>Visible 2D</title>

```



```
<property key="state" type="string">docked</property>
<property type="double" key="height">400</property>
<property type="double" key="width">600</property>
</gz-gui>
</plugin>
```

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```
<property key="state" type="string">docked</property>
<property type="double" key="height">400</property>
<property type="double" key="width">600</property>
</gz-gui>
</plugin>

</gui>

<plugin filename="gz-sim-contact-system" name="gz::sim::systems::Contact"/>
```

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Responses (1)



Write a response

What are your thoughts?



Christyj

Feb 1



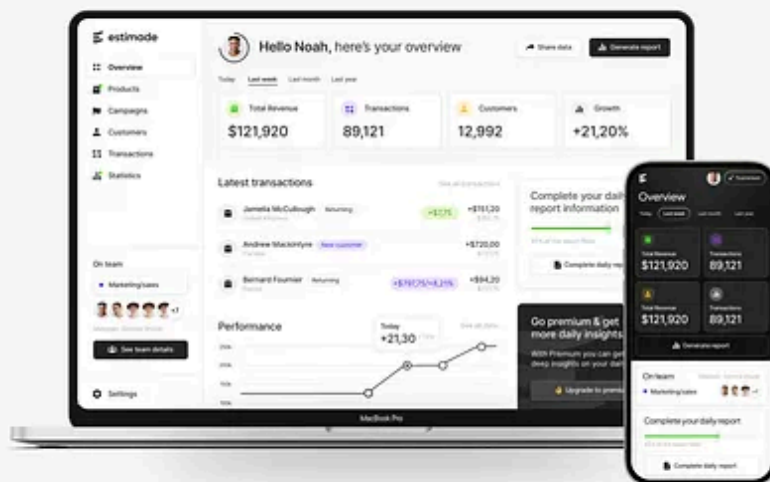
great content. can you explain how to choose the plugin and integrate it to a robot such that it can be visualized with rviz2 and the latest gz sim. Thanks





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ABSTRACT


Post-training alignment often reduces LLM diversity, leading to a phenomenon known as *mode collapse*. Unlike prior work that attributes this effect to algorithmic limitations, we identify a fundamental, pervasive data-level driver: *typicality bias* in preference data, whereby annotators systematically favor familiar text as a result of well-established findings in cognitive psychology. We formalize this bias theoretically, verify it on preference datasets empirically, and show that it plays a central role in mode collapse. Motivated by this analysis, we introduce **Verbalized Sampling (VS)**, a simple, training-free prompting strategy to circumvent mode collapse. VS prompts the model to verbalize a probability distribution over a set of responses (e.g., “Generate 5 jokes about coffee and their corresponding probabilities”). Comprehensive experiments show that VS significantly improves performance across creative writing (poems, stories, jokes), dialogue simulation, open-ended QA, and synthetic data generation, without sacrificing factual accuracy and safety. For instance, in creative writing, VS increases diversity by 1.6-2.1× over direct prompting. We further observe an emergent trend that more capable models benefit more from VS. In sum, our work provides a new data-centric perspective on mode collapse and a practical inference-time remedy that helps unlock pre-trained generative diversity.

Problem: Typicality Bias Causes Mode Collapse

Tell me a joke about coffee

Solution: Verbalized Sampling (VS) Mitigates Mode Collapse

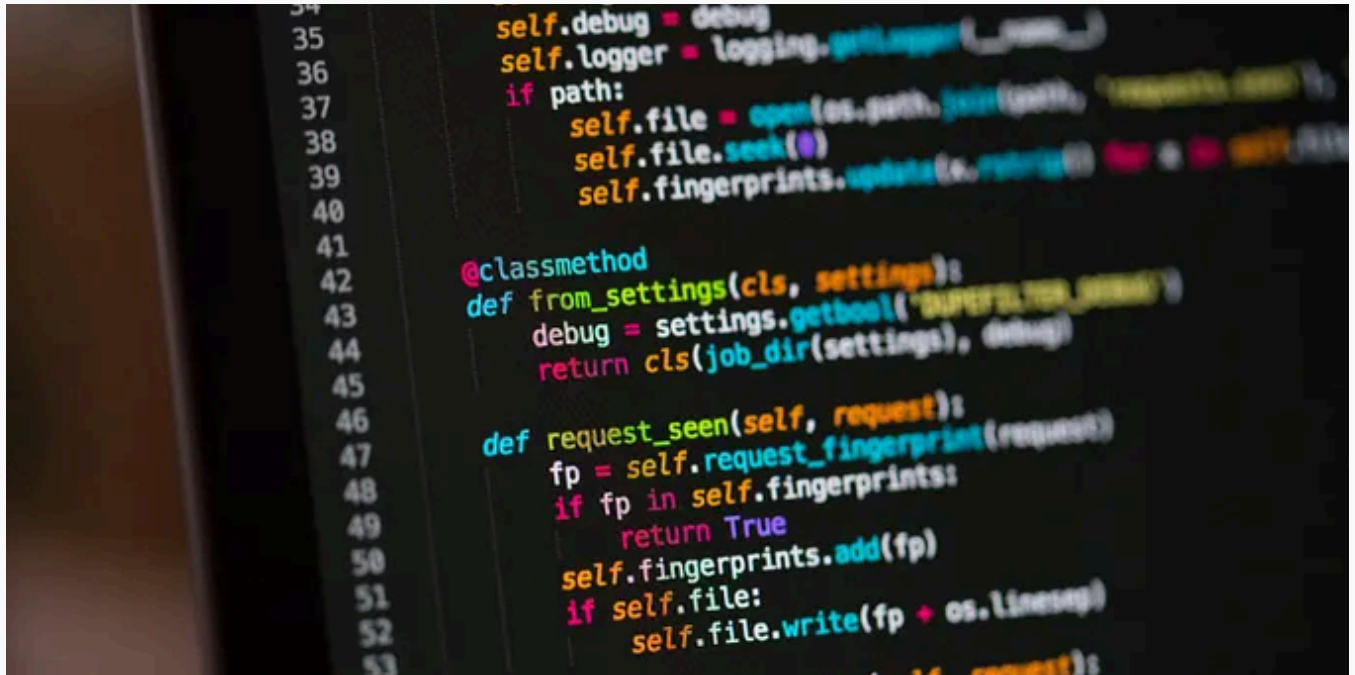
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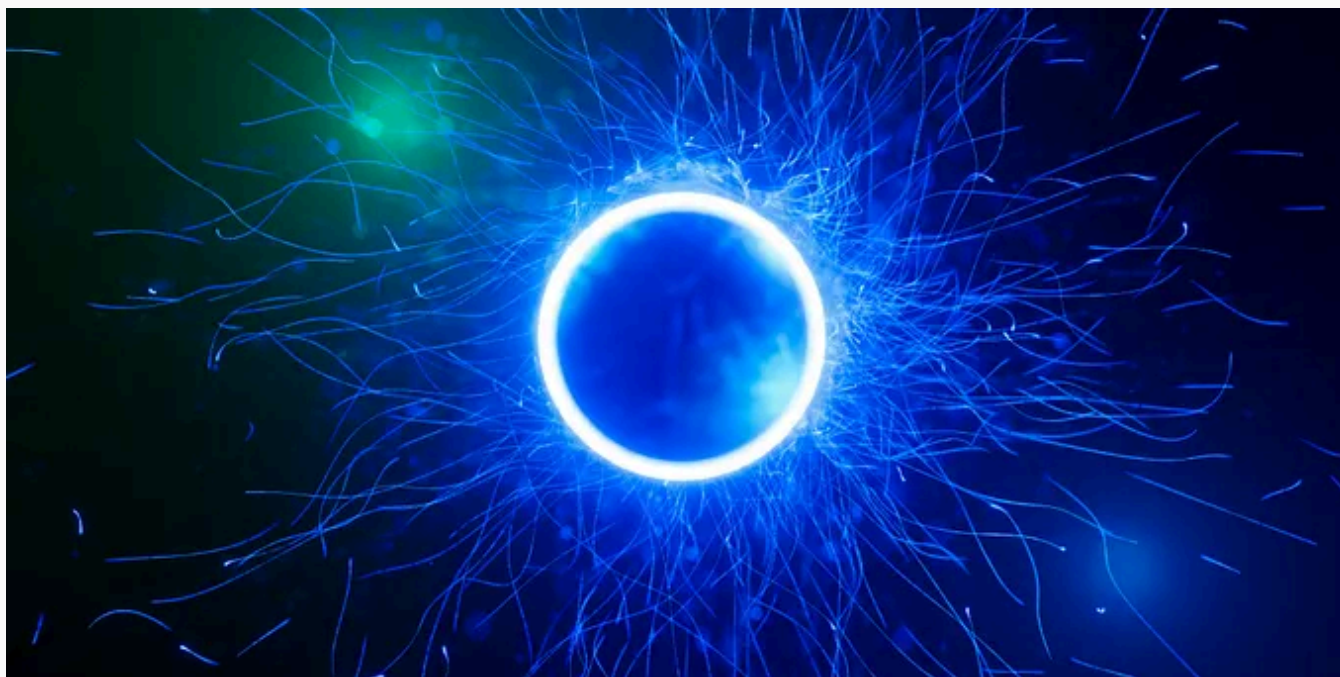
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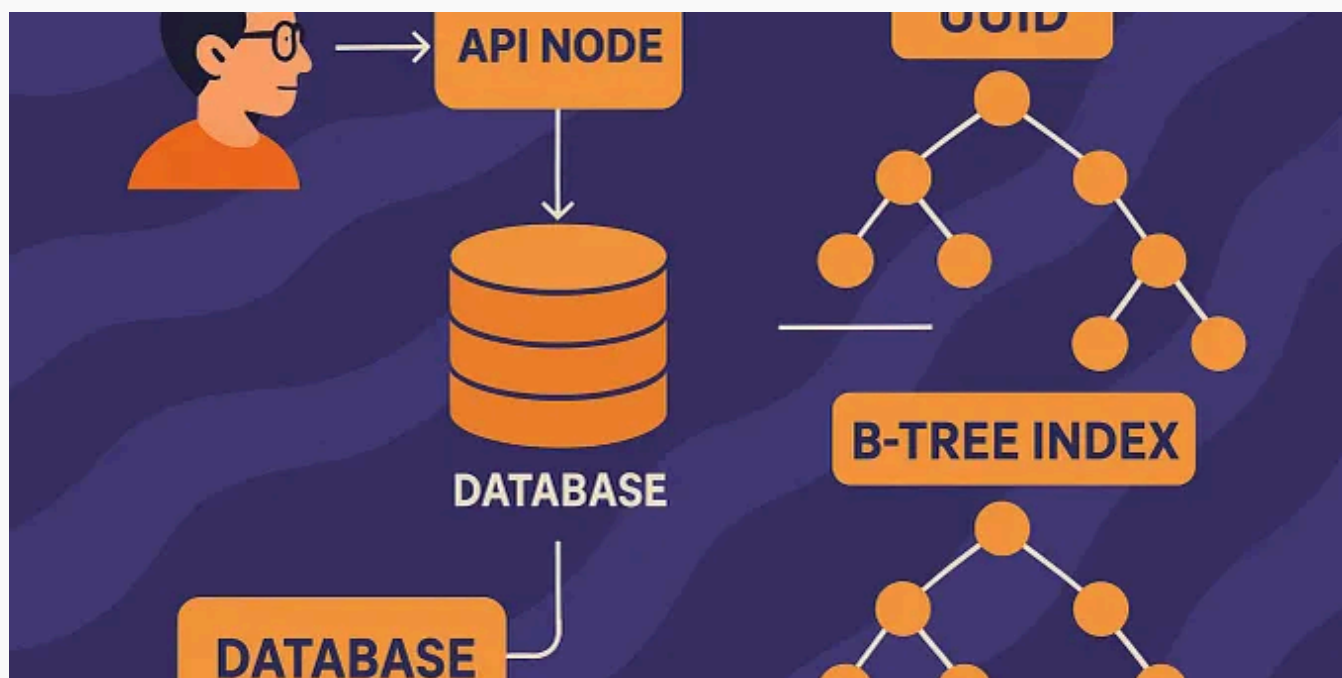


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