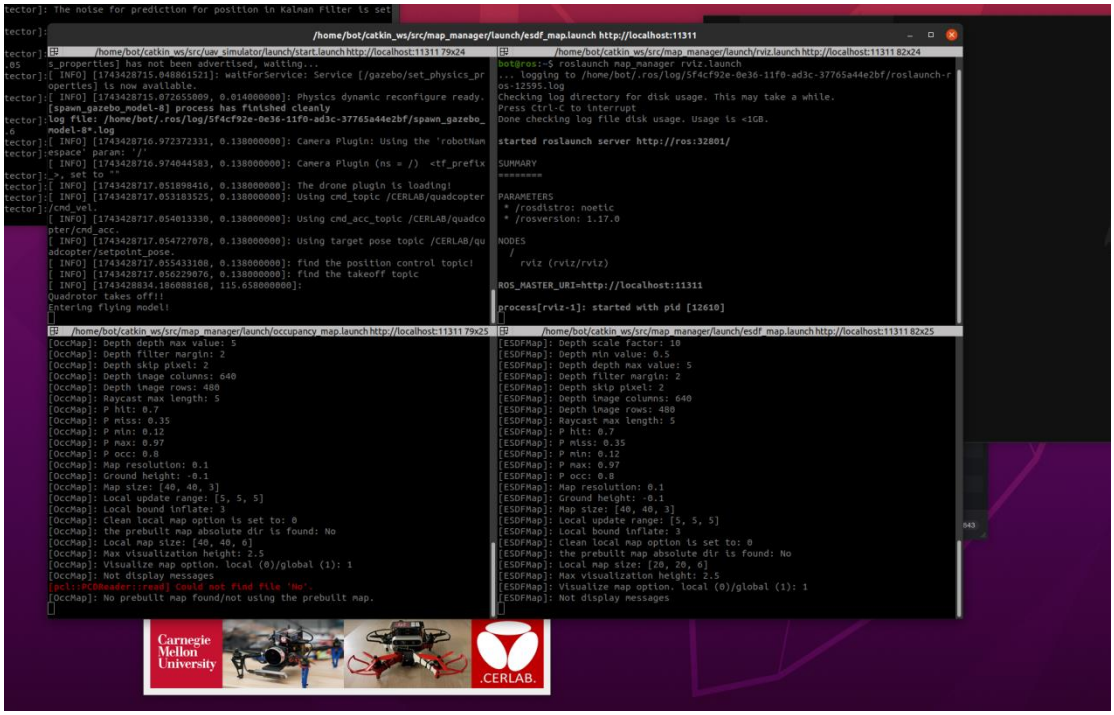
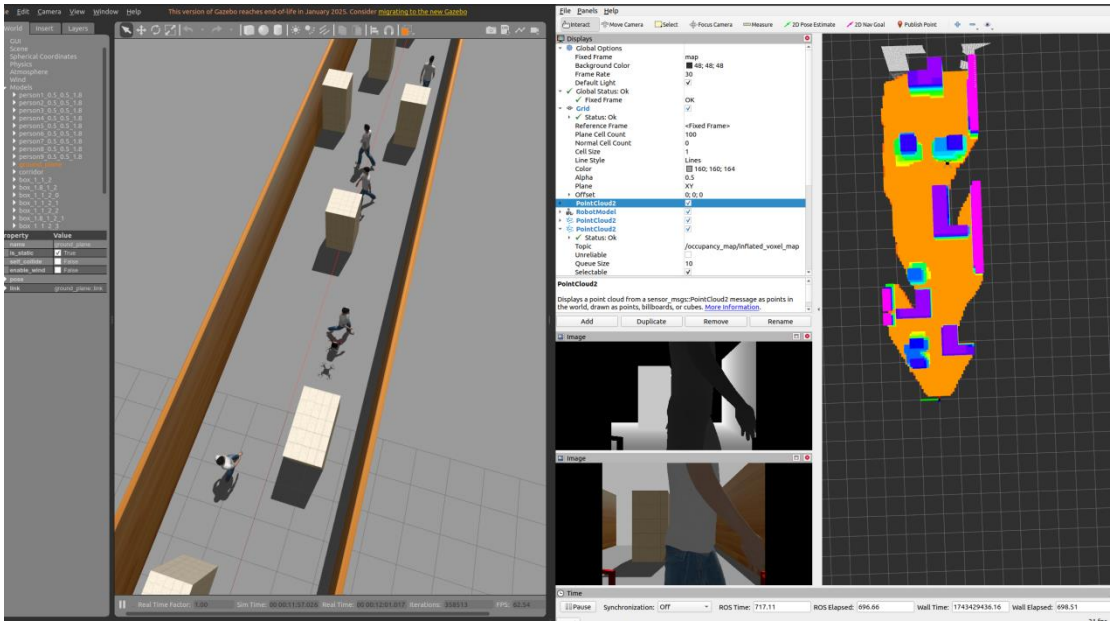
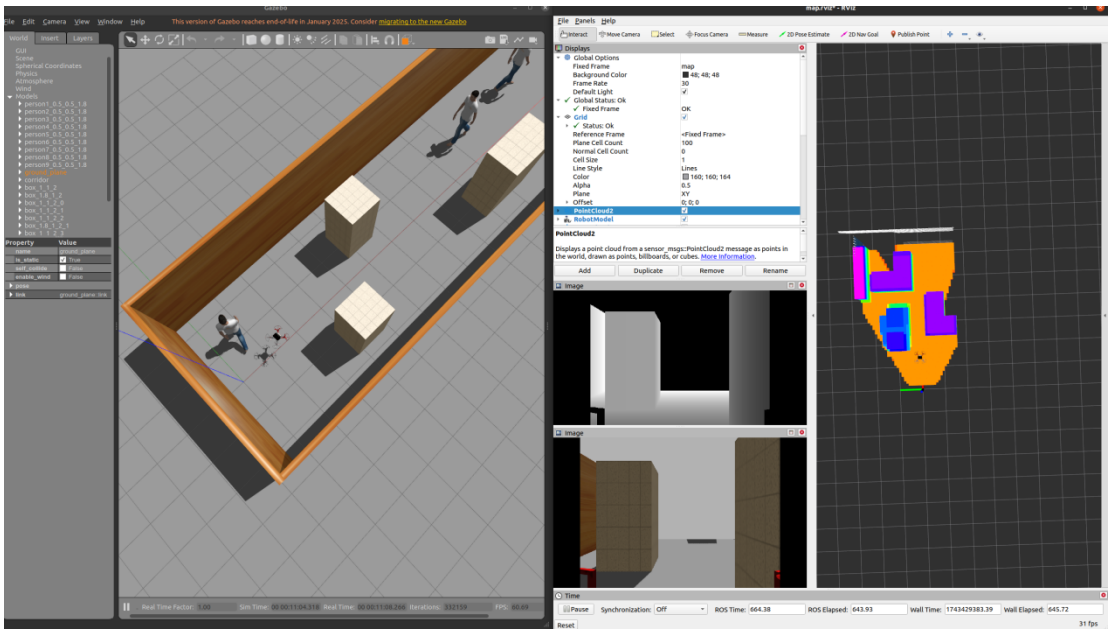
项目成功运行



障碍动态显示




Gazebo
File Edit Camera View Window Help
This version of Gazebo reaches end-of-life in January 2025. Consider migrating to the new Gazebo
World Insert Layers
GUI
Scene
Spherical Coordinates
Physics
Atmosphere
Wind
Models
person1_0.5_0.5_1.8
person2_0.5_0.5_1.8
person3_0.5_0.5_1.8
person4_0.5_0.5_1.8
person5_0.5_0.5_1.8
person6_0.5_0.5_1.8
person7_0.5_0.5_1.8
person8_0.5_0.5_1.8
person9_0.5_0.5_1.8
ground_plane
corridor
box_1_1_2
box_1.8_1_2
box_1_1_2_0
box_1_1_2_1
box_1_1_2_2
box_1.8_1_2_1
box_1_1_2_3
Property Value
name ground_plane
is_static True
self_collide False
enable_wind False
pose
link ground_plane::link
Real Time Factor: 1.00 Sim Time: 00 00:11:04.318 Real Time: 00 00:11:08.266 Iterations: 332159 FPS: 60.69
map.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 map
Background Color 48; 48; 48
Frame Rate 30
Default Light
Global Status: Ok
Fixed Frame OK
Grid
Status: Ok
Reference Frame <Fixed Frame>
Plane Cell Count 100
Normal Cell Count 0
Cell Size 1
Line Style Lines
Color 160; 160; 164
Alpha 0.5
Plane XY
Offset 0; 0; 0
PointCloud2
RobotModel
PointCloud2
Displays a point cloud from a sensor_msgs::PointCloud2 message as points in the world, drawn as points, billboards, or cubes. More Information.
Add Duplicate Remove Rename
Image
Image
Time
Pause Synchronization: Off ROS Time: 664.38 ROS Elapsed: 643.93 Wall Time: 1743429383.39 Wall Elapsed: 645.72
Reset
31 fps