

Lab 3 Assignment
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1. Assignment 1

a. **\$ rosrn tutorial assignment1.py**

Expected Result:

```
sean@sean-GP62-6QE:~/sis_lab_all/03-ROS_tutorial_1/catkin_ws/src/tutorial/src$ rosrn tutorial conver
t_pressure_unit.py
[INFO] [1537976203.162098]: Pressure: 754.35
[INFO] [1537976203.306014]: Pressure: 754.34
[INFO] [1537976203.444649]: Pressure: 754.38
[INFO] [1537976203.584188]: Pressure: 754.34
[INFO] [1537976203.727277]: Pressure: 754.34
[INFO] [1537976203.866601]: Pressure: 754.34
[INFO] [1537976204.010579]: Pressure: 754.35
```

Your Result:

```
NC(base) ndk@khoa:~/catkin_ws$ rosrn tutorial assignment1.py
[INFO] [1585222227.696335]: Pressure mmhg 754.27
[INFO] [1585222227.839410]: Pressure mmhg 754.35
[INFO] [1585222227.978942]: Pressure mmhg 754.33
[INFO] [1585222228.121724]: Pressure mmhg 754.29
[INFO] [1585222228.261504]: Pressure mmhg 754.28
[INFO] [1585222228.400806]: Pressure mmhg 754.32
[INFO] [1585222228.543933]: Pressure mmhg 754.34
[INFO] [1585222228.683041]: Pressure mmhg 754.29
```

b. **\$ rostopic list**

Expected Result:

```
sean@sean-GP62-6QE:~/sis_lab_all/03-ROS_tutorial_1/catkin_ws/src/tutorial/src$ rostopic list
/clock
/rosout
/rosout_agg
/sensor/pressure
/sensor/pressure_mmhg
/sensor/temp
```

Your Result:

```
(base) ndk@khoa:~/catkin_ws$ rostopic list
/clock
/rosout
/rosout_agg
/sensor/pressure
/sensor/pressure_mmhg
/sensor/temp
```

c. **\$ rostopic echo /sensor/pressure_mmhg**

Expected Result:

```
sean@sean-GP62-6QE:~/sis_lab_all/03-ROS_tutorial_1/catkin_ws/src/tutorial/src$ rostopic echo /sensor/
pressure_mmhg
data: 754.366929291
---
data: 754.344427444
---
data: 754.359428675
---
data: 754.389431138
---
```

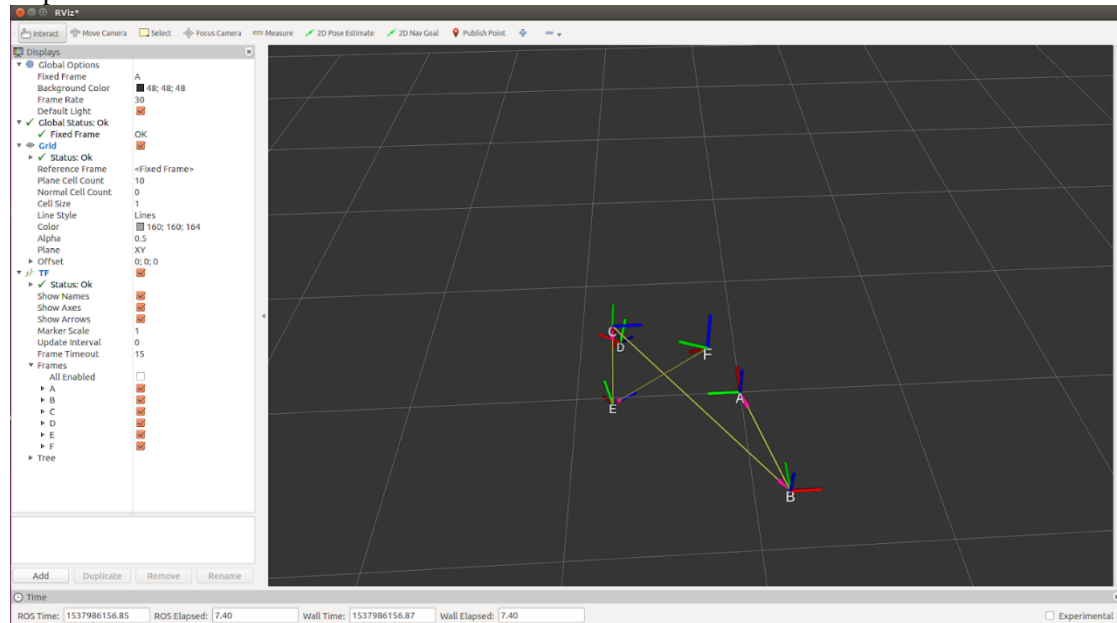
Your Result:

```
(base) ndk@khoa:~/catkin_ws$ rostopic echo /sensor/pressure_mmhg
data: 754.2675
---
data: 754.2375
---
data: 754.2975
---
data: 754.245
---
data: 754.245
---
data: 754.3125
```

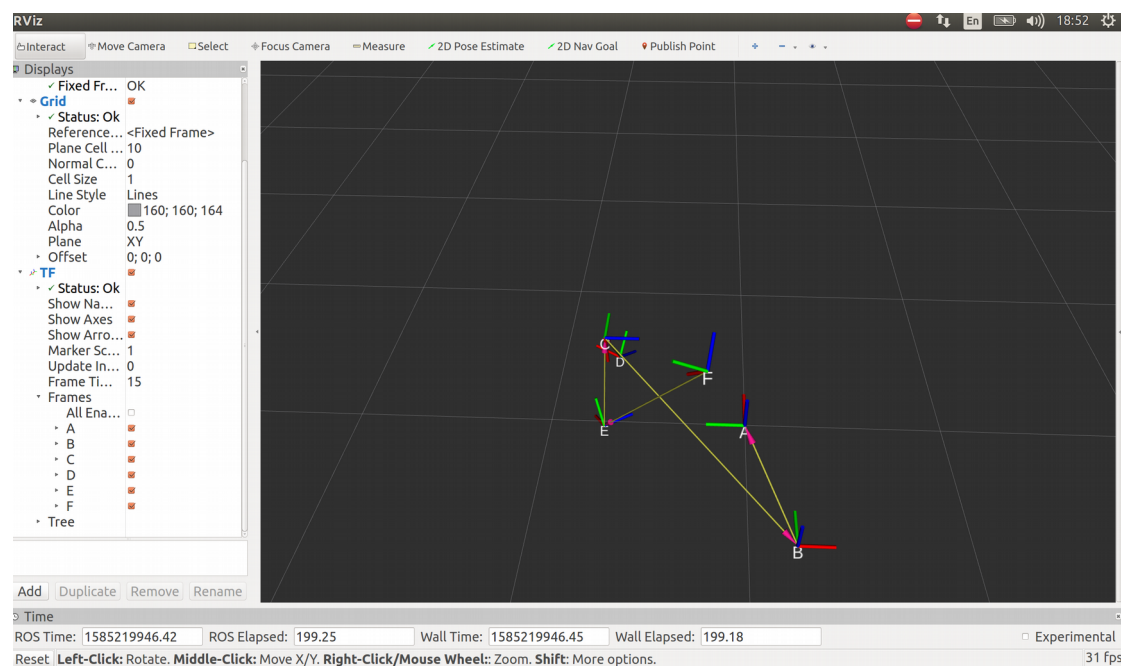
2. Assignment 2

a. `$ rviz -d tf.rviz`

Expected Result:



Your Result:



b. `$ rosrn tf tf_echo /B /F`

Expected Result:

```
sean@sean-GP62-6QE:~/sis_lab_all/03-ROS_tutorial_1/rviz$ rosrun tf tf_echo /B /F
At time 1537986248.888
- Translation: [-0.500, 0.500, 0.800]
- Rotation: in Quaternion [-0.191, 0.462, 0.733, 0.462]
           in RPY (radian) [0.785, 0.785, 2.356]
           in RPY (degree) [44.998, 45.002, 134.998]
At time 1537986248.888
- Translation: [-0.500, 0.500, 0.800]
- Rotation: in Quaternion [-0.191, 0.462, 0.733, 0.462]
           in RPY (radian) [0.785, 0.785, 2.356]
           in RPY (degree) [44.998, 45.002, 134.998]
```

Your Result:

```
^C(base) ndk@khoa:~/catkin_ws$ rosrun tf tf_echo /B /F
At time 1585221922.963
- Translation: [-0.500, 0.500, 0.800]
- Rotation: in Quaternion [-0.191, 0.462, 0.733, 0.462]
           in RPY (radian) [0.785, 0.785, 2.356]
           in RPY (degree) [44.998, 45.002, 134.998]
At time 1585221922.963
- Translation: [-0.500, 0.500, 0.800]
- Rotation: in Quaternion [-0.191, 0.462, 0.733, 0.462]
           in RPY (radian) [0.785, 0.785, 2.356]
           in RPY (degree) [44.998, 45.002, 134.998]
```

3. 注意事項

- 檔案名稱請改為 Lab3_assignment_學號_姓名，上傳格式請用 PDF
- 作業繳交期限為隔周四晚上 12 點前。
- 學生只要將作業要求的圖片更改為自己做實驗並截圖下來的圖片即可，無須多做說明。
- 截圖時除了預期結果之外也需要包含終端機的 user name 部份，否則助教會退件；另外請使用自己的 user name，若出現預設的 arg 也一律退件
- 請勿抄襲