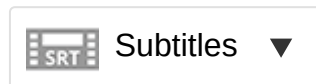


In the previous lecture, we have learned how to configure our logical camera plugin. Now, we will learn how to use the data the logical camera produces.

Logical camera accessing data



Subtitles (captions) in other languages than provided can be viewed at [YouTube](#). Select your language in the CC-button of YouTube.

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The logical camera outputs models and poses of objects. The poses contain position and orientation information which are defined in the reference frame of the camera. This information is published as a ROS Topic:

```
$ rosmmsg show hrwros_gazebo/LogicalCameraImage.msg -r  
$ rosmmsg show hrwros_gazebo/Model
```

The model message type has a string placeholder for the model name and a pose of the model itself.

ROS Topic contents for the logical camera:

Make sure the factory simulation is running, or launch it with:

```
$ roslaunch hrwros_gazebo hrwros_environment.launch
```

Print poses of the objects seen by the logical camera:

```
$ rostopic echo /hrwros/logical_camera
```

- The command publishes the models detected by the logical camera with their corresponding pose information.
- In the model sdf files, we define model names that will be used by the logical camera to publish the name information.
- The logical camera plugin can be configured to only publish objects that are known. But we will not do this.

Question 1

1 point possible (ungraded)

Which of the following statements is true with respect to the information from Logical camera?

☐ The logical camera image data contains an array of models detected by the logical camera.

☐ The pose information is only the camera pose in the world and actually not the objects detected by the Logical Camera.

☐ The logical camera publishes information on a ROS Topic and that topic has the LogicalCameraImage message type.

☐ The logical camera publishes pose messages with timing and header information.

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