



# CAOCM Auscultation

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# Embed our code into the actual functioning code.

01.

The input isn't a ply file, but a pointcloud2 stream instead.

Q: Which image does the subscriber process with due to the time differentiation of processing and providing?

02.

Change the input Pointcloud2 datatype into open3d datatype.

03.

The output should be in quaternion form so the robotic arms can move directly.

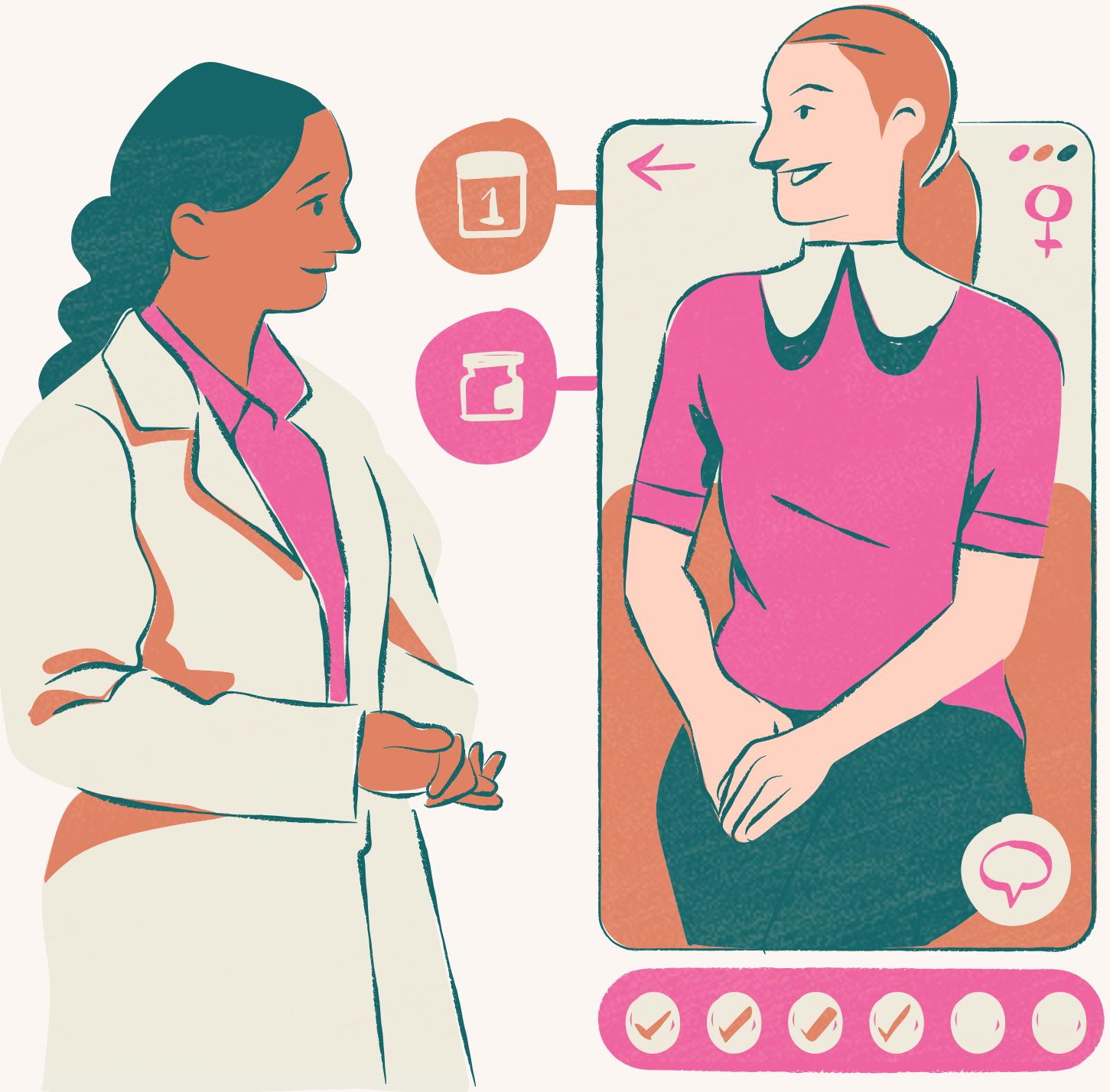
# What we need to know

1. Receive the desired point coordinate or its index.
2. Linear transformation matrix from the camera coordination system to the robotic arm's coordination system.
3. The default direction for calculating quaternion.



# What we need to do more

- After calculating the normal vector(Quaternion), we need to publish it to the subscriber.
- Testing the robotic arm's performance!
- Fine Tuning the algorithm(Hopefully we can do it well in the first time.)



TUM



Thank you  
very  
much!



# Notes

- tf2 library