ROS Manual

Support Models: MTF SDK

Version 0.0.1 – July 24th, 2019

History

Date	Version	Contents	
19.07.24	0.0.1	The first written	

MTF SDK Driver

These are packages for using MTF Module with ROS.

Installation Instructions

The following instructions support ROS Kinetic, on **Ubuntu 16.04**.

Step 1 : Install the ROS distribution

- Install ROS Kinetic, on Ubuntu 16.04

Step 3 : Install driver

- Create a catkin workspace

```
$mkdir –p ~/catkin_ws/src
$cd ~/catkin_ws/src/
Copy the driver source to the path(catkin_ws/src)
```

- driver build

```
$catkin_init_workspace
$cd..
$catkin_make clean
$catkin_make -DCMAKE_BUILD_TYPE=Release
```

- Setting environment

```
$sudo mtfinstall.sh
```

Usage Instructions

Start the camera node

Connect the camera power and execute the following command

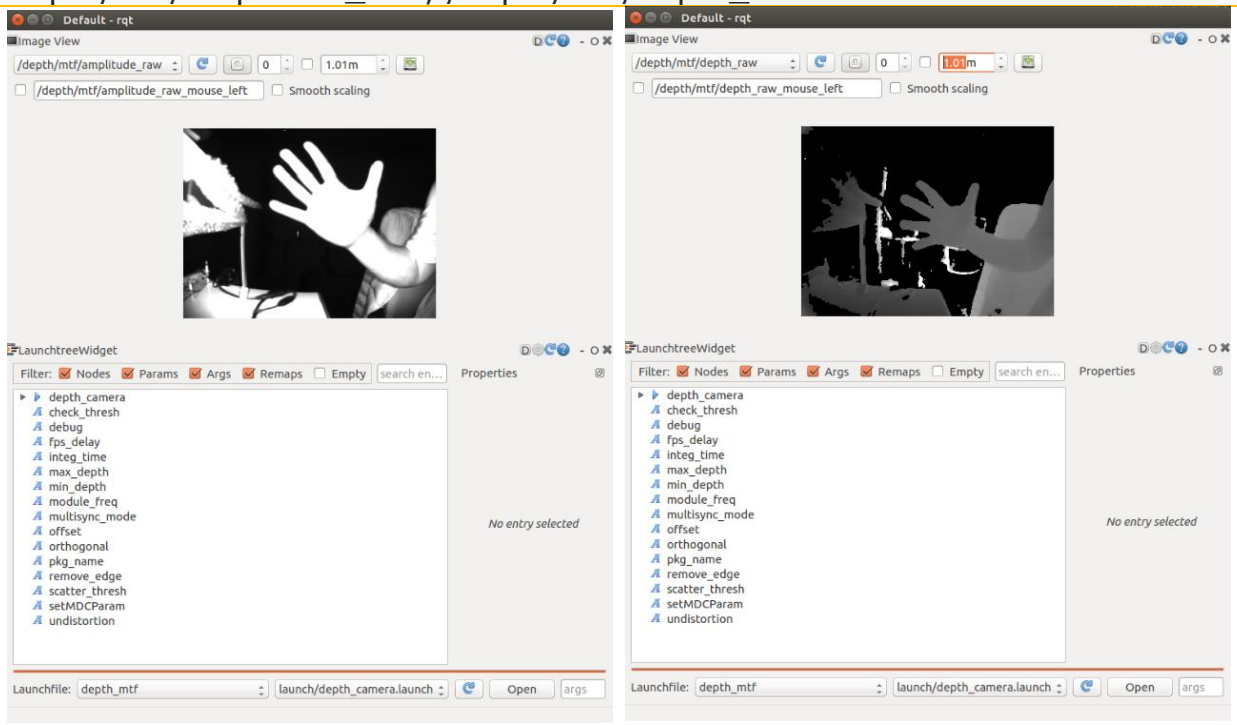
```
$roslaunch depth_mtf depth_camera.launch
```

Topics

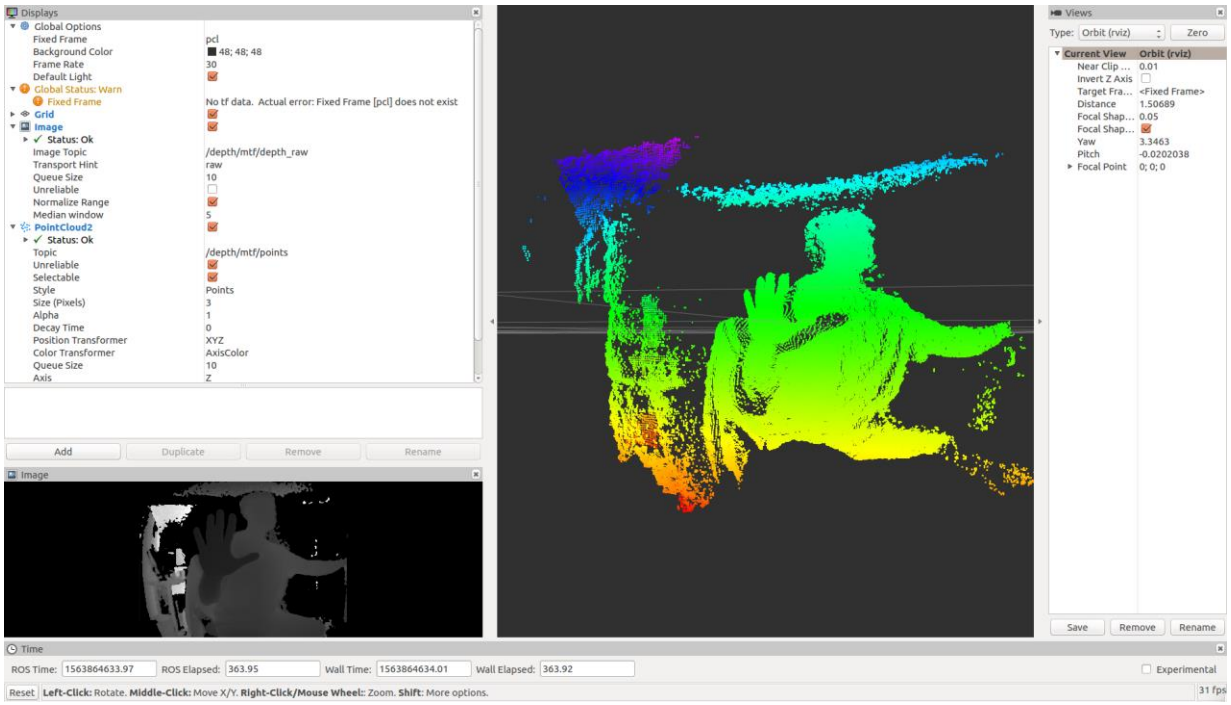
- /depth/mtf/amplitude_raw : IR Image
- /depth/mtf/depth_raw : Depth Image
- /detph/mtf/points : Point Cloud Image

Operating Test

```
$rqt
/depth/mtf/amplitude_raw, /depth/mtf/depth_raw
```



```
$rosrun rviz rviz
Fixed Frame : pcl
PointCloud2 : /depth/mtf/points
```



Using Dynamic Reconfigure Params

```
rosrun rqt_reconfigure rqt_reconfigure
```