

# Assignment #5

[Rviz, tf\_echo, tf\_tree, tf\_broadcaster]

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## 1) Rviz

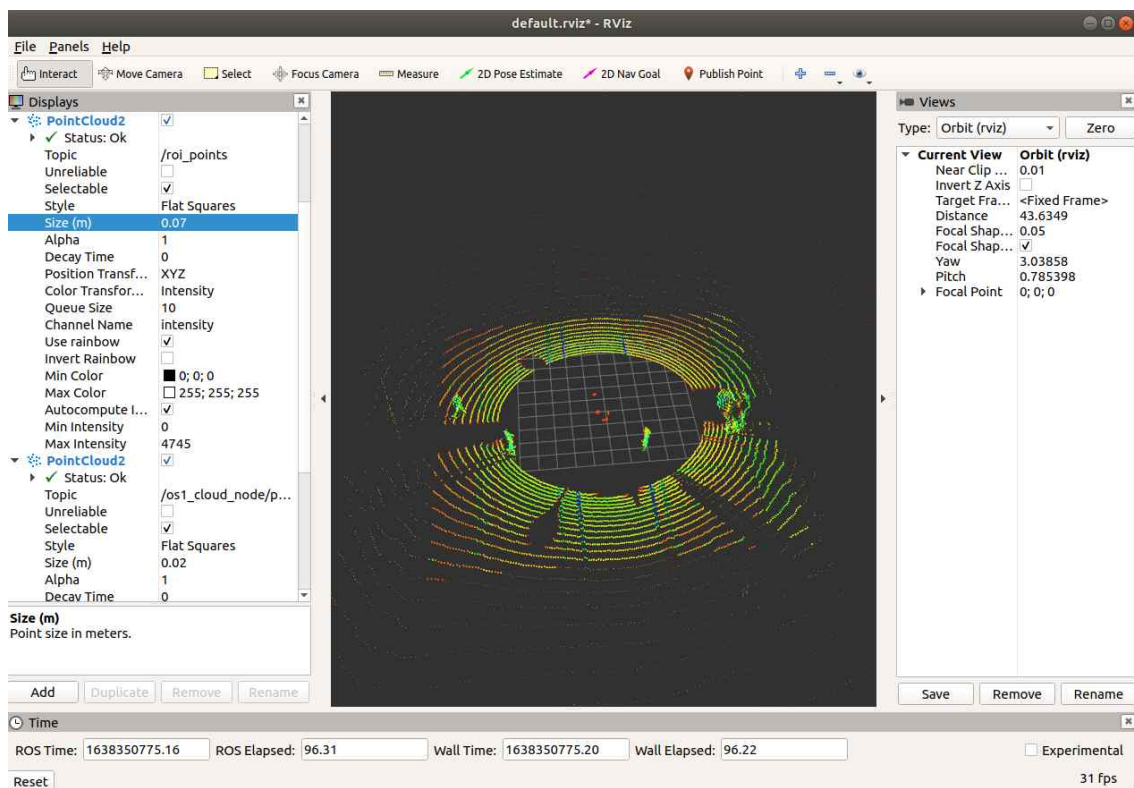
### 1.1) 소스코드

pcl 패키지 첨부하였습니다.

### 1.2) pcl 패키지의 pcl 노드 실행 : rosrn pcl pcl

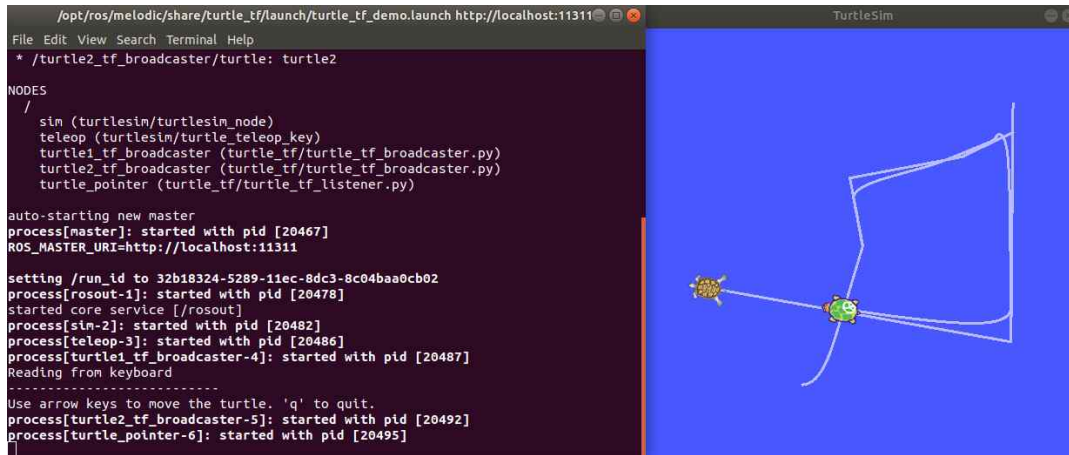
### 1.3) rviz

ROI pointcloud size : 0.07

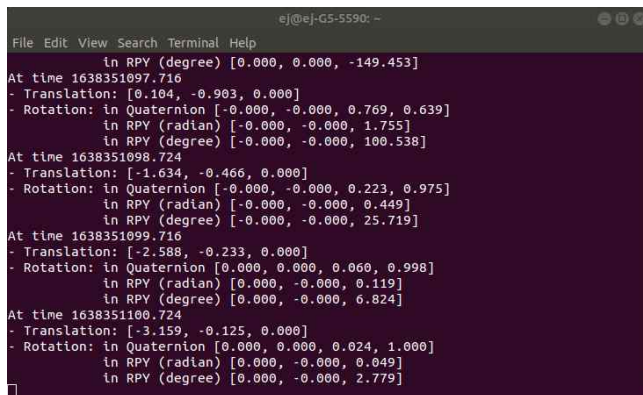


## 2) tf\_echo, tf\_tree

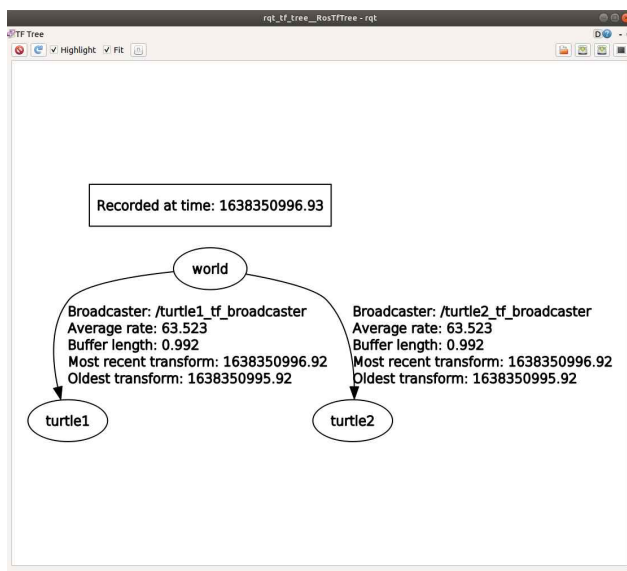
### 2.1) Turtle\_tf demo : roslaunch turtle\_tf turtle\_tf\_demo.launch



### 2.2) tf 정보 확인 : rosrun tf tf\_echo turtle1 turtle2



### 2.3) tf tree 확인 : rosrn rqt\_tf\_tree rqt\_tf\_tree



### 3) tf\_broadcaster

#### 3.1) 소스코드

learning\_tf 패키지 첨부하였습니다.

#### 3.2) learning\_tf 패키지의 launch 파일 실행 : roslaunch learning\_tf start\_demo.launch

