



The **Map** display shows a `nav_msgs/OccupancyGrid` (http://docs.ros.org/en/api/nav_msgs/html/msg/OccupancyGrid.html) message. The occupancy grid is treated the way the navigation (/navigation) stack treats it. A value of 100 is black (occupied), a value of 0 is white (unoccupied), and anything else is gray (unknown).

rviz map display type



Properties

Name	Description	Valid Values	Default
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Topic	The topic to subscribe to	Any valid Graph Resource Name (/Names#Graph)	Empty String
Alpha	The amount of transparency to apply to the map	[0-1]	1
Request Frequency	How often to re-request the map, in seconds. A value of 0 means to never re-request the map.	0+	0

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