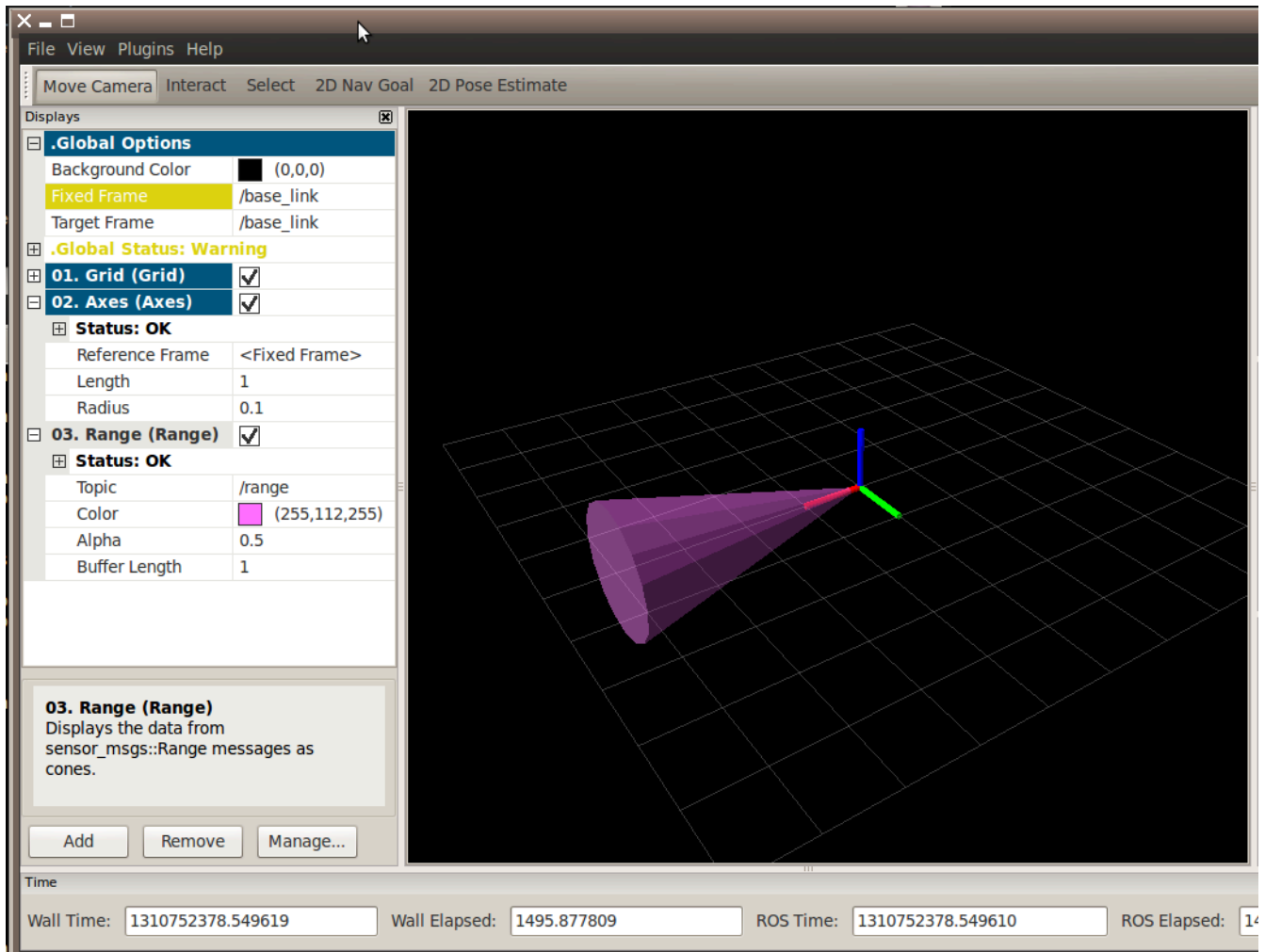


New in Electric



The **Range** display shows range measurements. Each one is a cone starting at the origin of the frame given in the header of the `sensor_msgs/Range` (http://docs.ros.org/en/api/sensor_msgs/html/msg/Range.html) message and fanning out in the +X direction of that frame.

To display multiple ranges (like from a robot with several sonars), publish a TF frame at each sonar location. Publish the range messages with the corresponding `frame_id` in each header. Then in rviz, in the Range display properties, set "Buffer Length" to the number of range sensors on your robot.

Properties

Name	Description	Valid Values	Default
Topic	The topic on which to listen for Range messages.		
Color	The color of the range cones		

Alpha	Opacity of the range cones, 0 is transparent, 1 is opaque.	0-1	0.5
Buffer Length	The number of range measurements to show on this topic. Only the most recent (Buffer Length) cones will be shown.	1+	1

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