

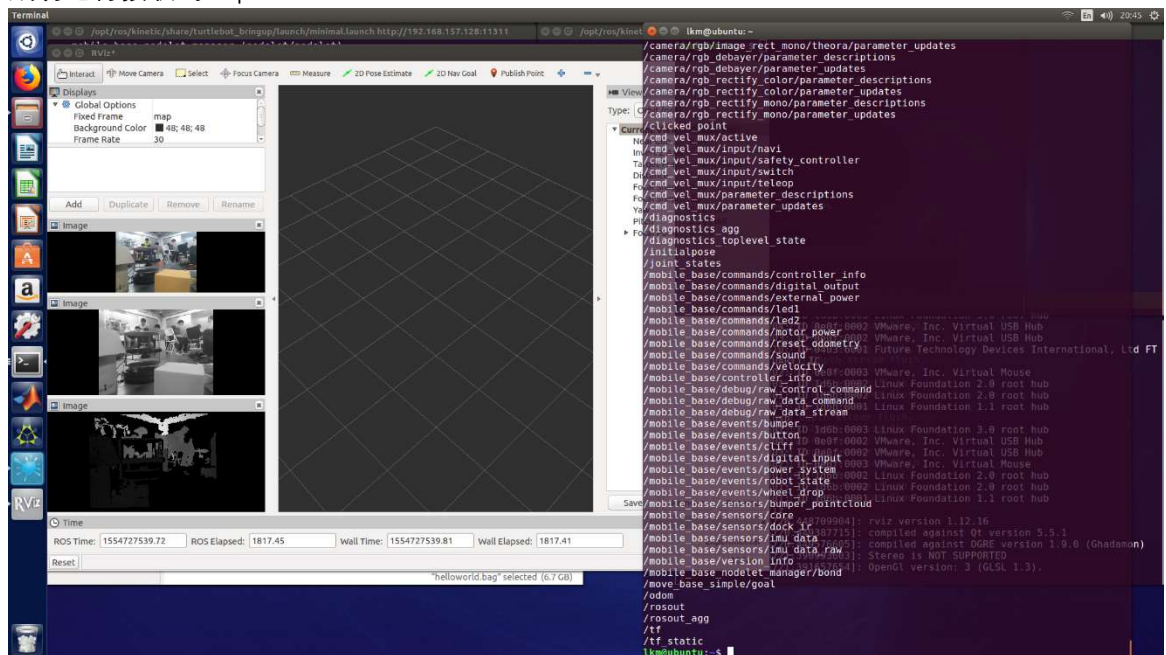
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1. 流程

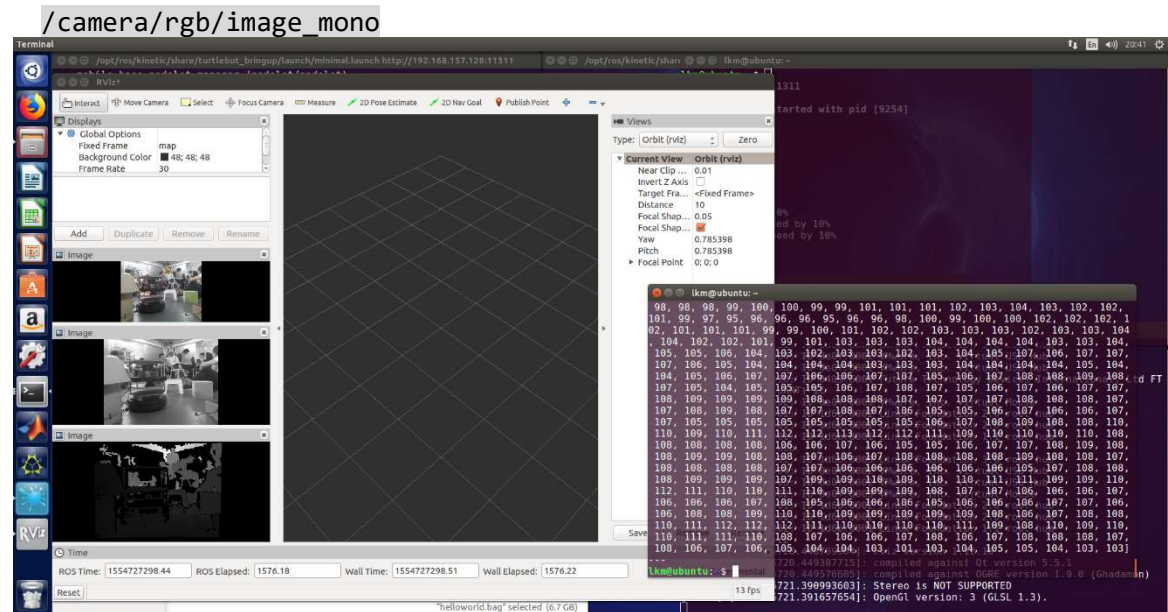
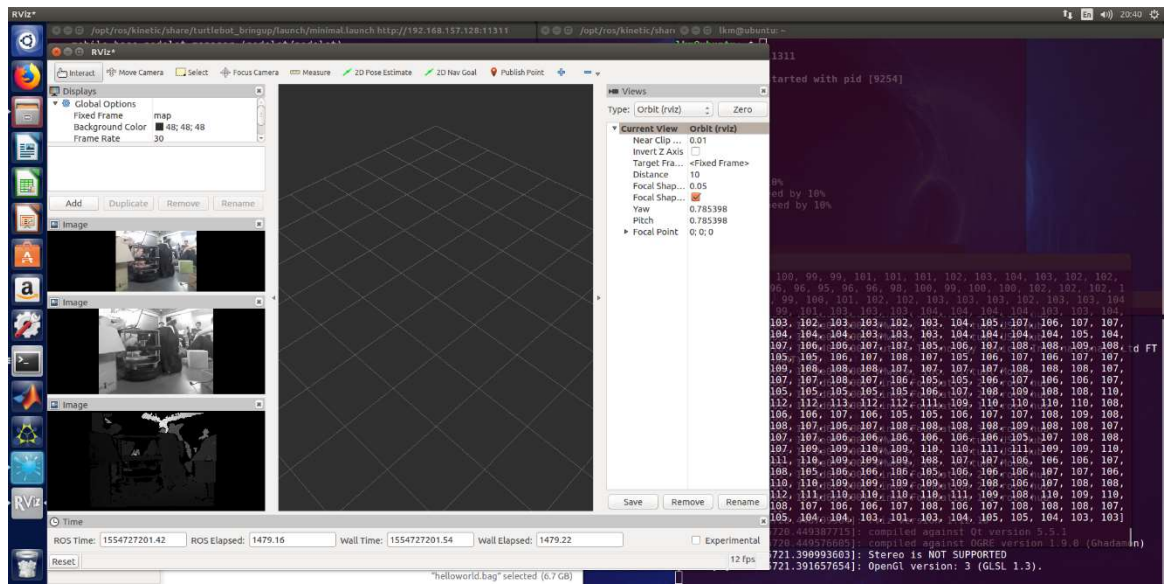
- (1) `roslaunch turtlebot_bringup minimal.launch` 连接机器人
- (2) `roslaunch turtlebot_teleop keyboard_teleop.launch` 利用按键控制机器人移动
- (3) `roslaunch freenect_launch freenect-registered-xyzrgb.launch` 连接相机

2. 成功运行接收到 topic



3. Topic echo result

`/camera/rgb/image_color`

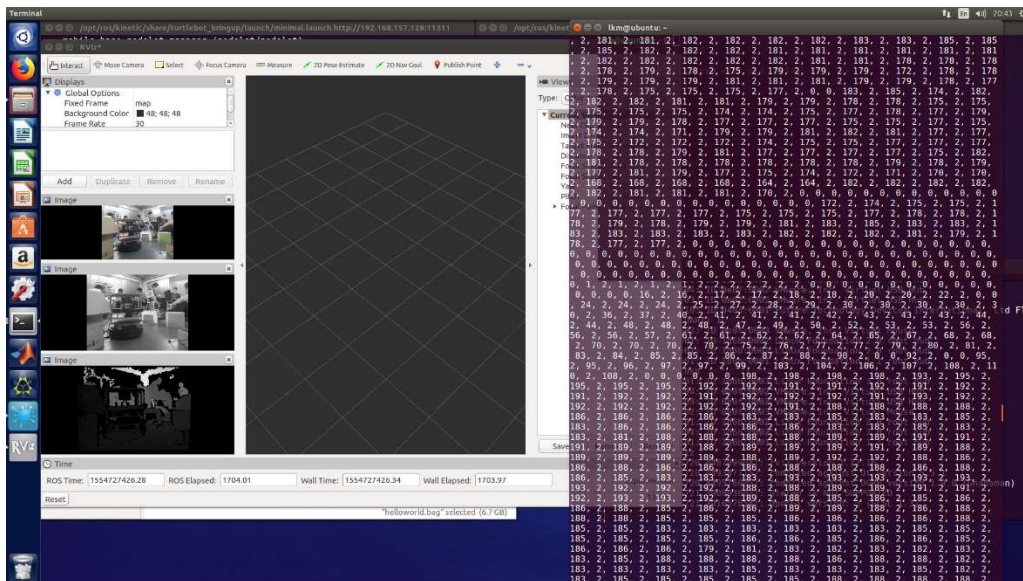


4. Topic graph

```

/camera/rgb/image_color
/camera/depth_registered/image_raw
/camera/rgb/image_mono

```



5. Meaning of each topic

/camera/rgb/image_color 彩色像素点

/camera/depth_registered/image_raw 深度图像素点

/camera/rgb/image_mono 单色像素点

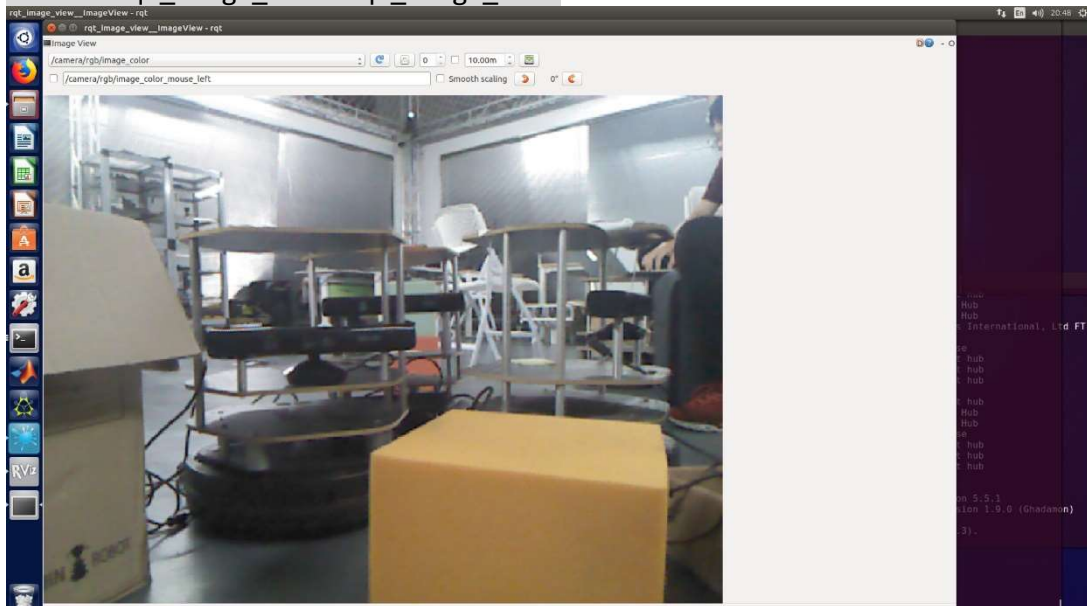
/odom odometry 相关的内容

/tf **Transformation** Tree

tf is a package that lets the user keep track of multiple coordinate frames over time. tf maintains the relationship between coordinate frames in a tree structure buffered in time, and lets the user transform points, vectors, etc between any two coordinate frames at any desired point in time.

/tf_static For greater efficiency tf now has a static transform topic "/tf_static". This topic has the same format as "/tf" however it is expected that any transform on this topic can be considered true for all time. Internally any query for a static transform will return true.

6. rosrn rqt_image_view rqt_image_view



Other topic result is in part 4 with small graphs

遇到的问题：

相机连不上

问题所在：

相机的连接线有问题

解决办法

等其他组做完借他们的设备完成