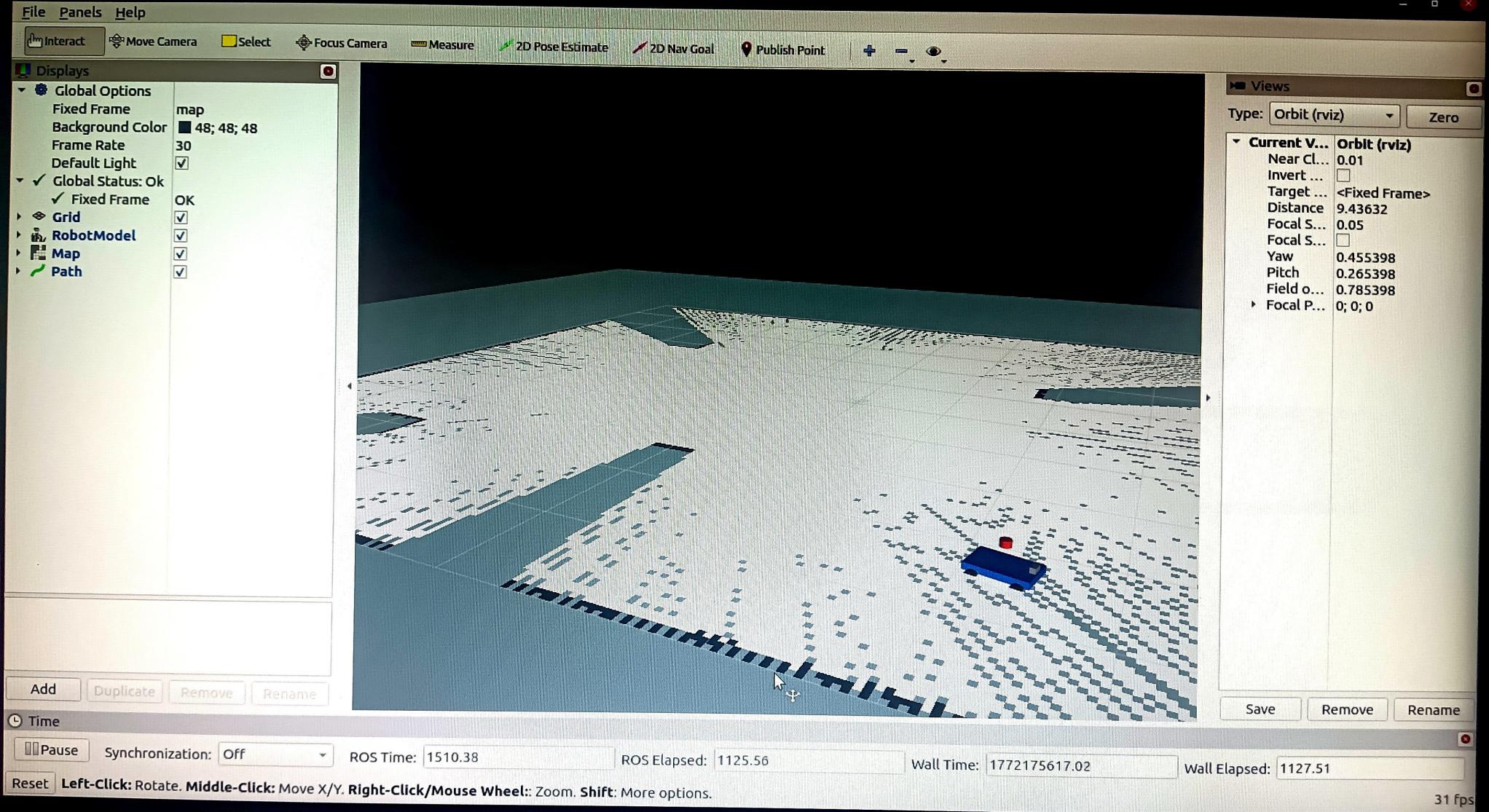


Activities

RVIZ

Feb 27 12:30

default.rviz* - RViz



Feb 27 12:30

default.rviz* - RViz

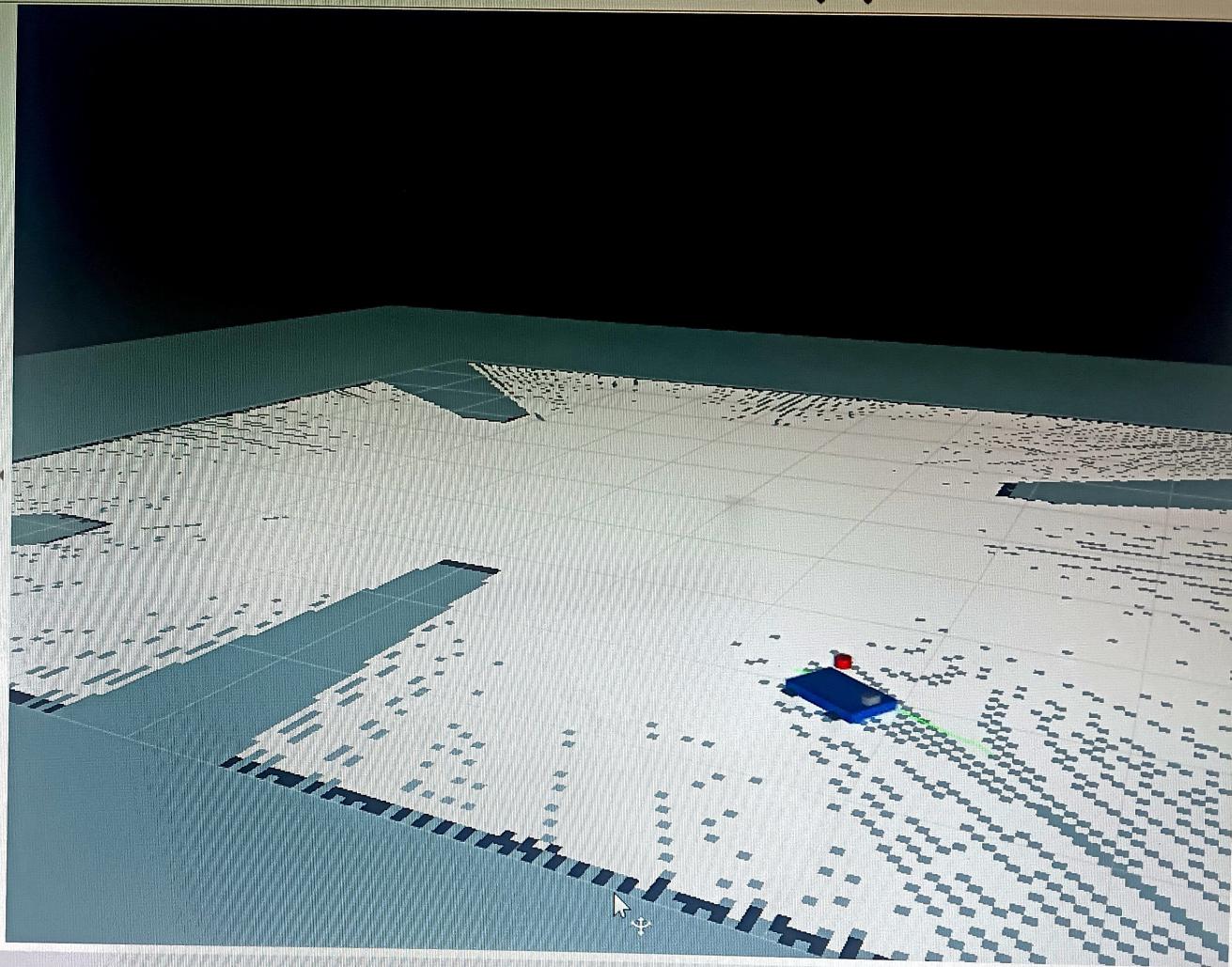
File Panels Help

Interact Move Camera Select Focus Camera Measure 2D Pose Estimate 2D Nav Goal Publish Point

Displays

Global Options

Fixed Frame	map
Background Color	[48; 48; 48]
Frame Rate	30
Default Light	<input checked="" type="checkbox"/>
✓ Global Status: Ok	
✓ Fixed Frame	OK
Grid	<input checked="" type="checkbox"/>
RobotModel	<input checked="" type="checkbox"/>
Map	<input checked="" type="checkbox"/>
Path	<input checked="" type="checkbox"/>



Views

Type:	Orbit (rviz)
Near Cl...	0.01
Invert ...	<input type="checkbox"/>
Target ...	<Fixed Fr...
Distance	9.43632
Focal S...	0.05
Focal S...	<input type="checkbox"/>
Yaw	0.455398
Pitch	0.265398
Field o...	0.785398
Focal P...	0; 0; 0

Add Duplicate Remove Rename

Time

Pause

Synchronization: Off

ROS Time: 1507.80

ROS Elapsed: 1123.04

Wall Time: 1772175614.50

Wall Elapsed: 1124.95

Left-Click: Rotate. Middle-Click: Move X/Y. Right-Click/Mouse Wheel: Zoom. Shift: More options.



Activities

Terminal ▾



File Edit Camera View Window Help

World Insert Layers
Spherical Coordinates
Physics
Atmosphere
Wind
Models

railab@r... Q X

```
-Desktop-PC:~/arjuna_sim$ rosrun arjuna_gazebo teleop_key.py
```

Arjuna Teleop - Keyboard

w = forward
s = backward
a = turn left
d = turn right
x = STOP
q = quit

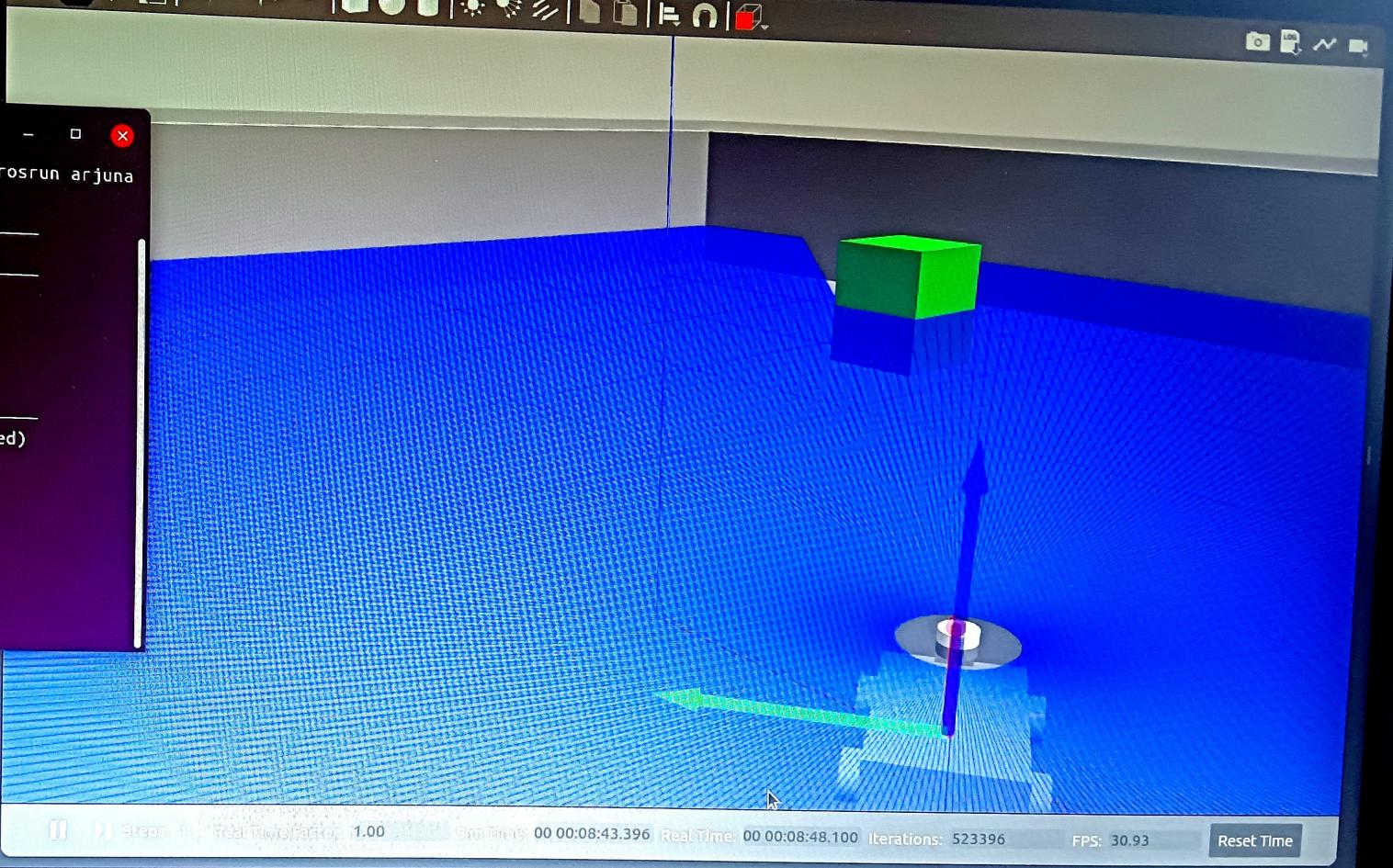
Press a key (no Enter needed)

FORWARD
FORWARD
FORWARD
FORWARD
FORWARD
FORWARD
TURN LEFT
TURN RIGHT

This version of Gazebo reaches end-of-life in January 2025. Consider [migrating to the new Gazebo](#).

Feb 26 16:16

Gazebo



Feb 25 17:01

default.rviz* - RViz

Activities rviz



File Panels Help

Interact Move Camera Select Focus Camera Measure 2D Pose Estimate 2D Nav Goal Publish Point

Displays

Global Options
Fixed Frame laser
Background Color 48; 48; 48
Frame Rate 30
Default Light ✓
Global Status: ...
Fixed Frame No TF data
Grid
LaserScan
Status: Ok
Topic /scan
Unreliable
Queue Size 10
Selectable ✓
Style Flat Squares
Size (m) 0.01
Alpha 1
Decay Time 0
Position Transf... XYZ
Color Transf... Intensity
Channel Name intensity
Use rainbow ✓
Invert Rainbow
Min Color 0; 0; 0
Max Color 255; 255; 255
Autocompute I... ✓
Min Intensity 3
Max Intensity 53

Topic
sensor_msgs/LaserScan topic to subscribe to.

Add

Time

Pause

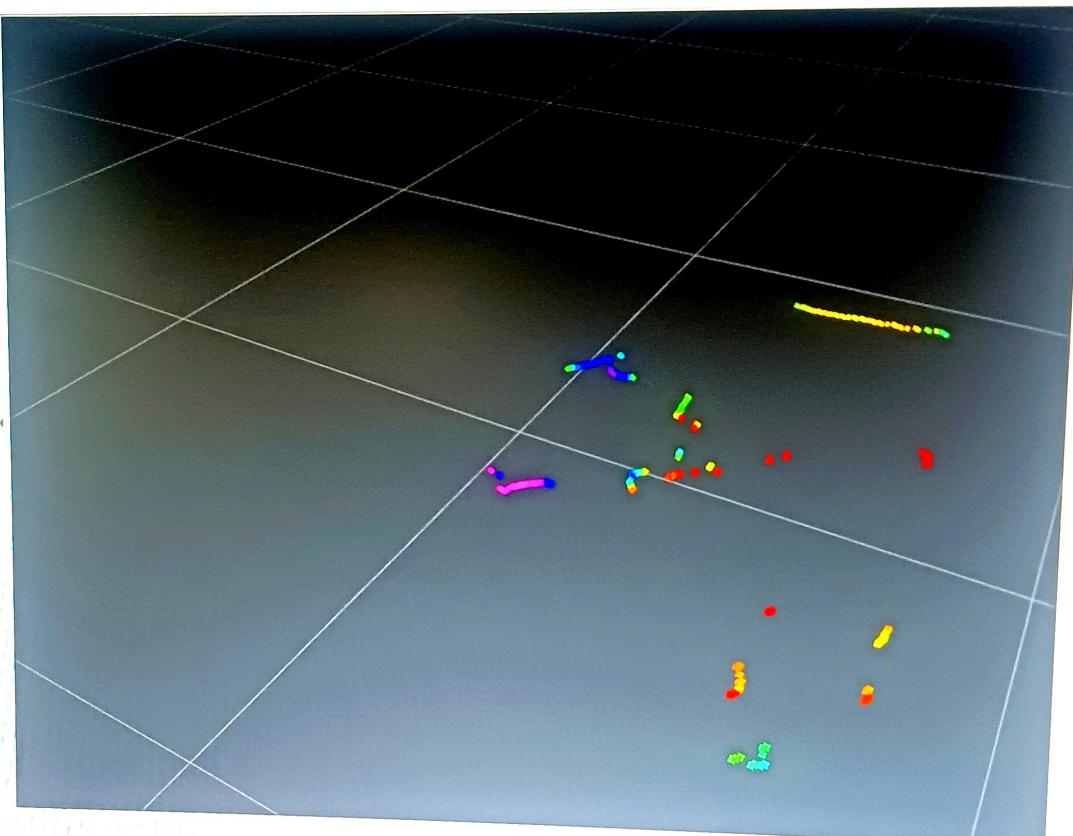
Synchronization: Off

ROS Time: 1772019073.74

ROS Elapsed: 688.22

Wall Time: 1772019073.77

Wall Elapsed: 688.16



Views

Type: Orbit (rviz) Zero
Current V... Orbit (rviz)
Near Cl... 0.01
Invert ...
Target ... <Fixed Frame>
Distance 2.1199
Focal S... 0.05
Focal S... ✓
Yaw 2.0754
Pitch 0.615398
Field o... 0.785398
Focal P... 0; 0; 0
Orbit Orbit (rviz)

Save

Remove

Rename

31 fps