

What is the correct orientation of RPLidar? #77

New issue

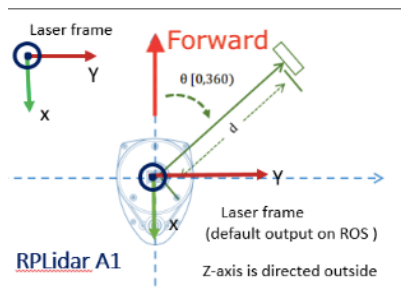


subodh-malgonde opened this issue on Oct 24, 2018 · 2 comments



subodh-malgonde commented on Oct 24, 2018 • edited ▾

I want to install the sensor on my robot such that there is no transform from base_link to laser i.e. no translation and no rotation. Should the tapering end of the sensor be facing the back of my robot, as shown in the picture?



Or should I place it the other way round?

Assignees

No one assigned

Labels

None yet

Projects

None yet

Milestone

No milestone

3 participants



GYKrauss commented on Jan 9

The green arrow marked "x" is facing downwards. This means that the motor end is really the "front." If you want to avoid any tf, it must be placed "backwards."



kintzhao commented on Jan 15

Collaborator

keep your any install by configure your TF-tree frame: base_link -> laser

such as: [\(13/57\)](#)



kintzhao closed this on Jan 15