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how does the odometry (imu+encoder) publish its data to gmapping?

gmapping   odometry

I am able to get my odometry working (with IMU and encoders readings). But how do i actually publish the relevant data to gmapping? Is the gmapping file actually subscribing any data from the odometry?

asked Jul 16 '13
Andrick
21 ●4 ●4 ●6

updated Nov 19 '13
tfoote 🇺🇸
52980 ●101 ●366 ●458
http://www.ros.org/

Comments

Hı, Mr. @Andrick . Coul you please help me how to merge ımu andencoder data?
🔲 Mekateng (**Jun 7 '18**)

how did you get odometry working can you share
⬚ kallivalli (**Sep 17 '19**)

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0

To answer questions of this nature, it is always good to refer to the package itself: gmapping subscribed topics

link

answered Jul 16 '13
weiin
2168 ●26 ●43 ●64

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2

Hey,

Basically as Weiin said the Gmapping

answered Jul 17 '13
HenryW
130 ●5 ●6 ●14

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link shows that Gmapping is subscribed to tf/tfMessage to get its odometer information.

You need to publish the odometer information as both a nav_msgs/Odometry and a tf/tfMessage. A good tutorial explaining this can be found here

http://www.ros.org/wiki/navigation/Tutorials/RobotSetup/Odom

link

Comments

3 You do not need the odometry message for gmapping. It gets that data through the tf. (You do however, need the odometry message for the navigation stack.)

weiin (**Jul 17 '13**)

Yes sorry Weiin is correct, Gmapping does not need it itself :D

HenryW (**Jul 18 '13**)

Alright thanks! I'll have to read more about the tf then! :)

Andrick (**Jul 18 '13**)

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