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how to sync two ROS topics by adjusting the time stamp

ROS_Topic_Sync

rosbag

Actual Issue: I have a topic published with images from a camera and another topic with details of point cloud. When I plot these two topics, there is a time lag between the two plots. Is there any method to synchronize this time lag by adjusting the time stamp of point cloud message?

asked May 13 '16

A G
18 ●2 ●3 ●5

updated May 18 '16

I am using rosbag play for the above mentioned purpose.

Re-creating the Scenario I tried to simulate the above scenario using the below mentioned points: i. Created a subscriber node which subscribe to the topic(/point_cloud) with point cloud data. ii. Inside the callback function, I copied the message to a new pointer variable of the same type (sensor_msgs::PointCloud2) and incremented the timestamp by 3sec (The debug print shows that the timestamp has been successfully updated). iii. Then I published the modified point cloud data in a new topic(/point_cloud_new). iv. Created two instances of rviz which subscribes to the two topics, /point_cloud and /point_cloud_new respectively. v. Since the timestamp of /point_cloud_new was incremented by 3sec, I expected a 3sec delay between the two plots in the rviz. But it is not happening.

Since I am new to ROS, I am not sure whether it is the correct method to approach this issue. Please comment on the actual issue and the scenario re-created.

Please help me to sort out this issue.

Comments

When you play the bag file are you setting the parameter `use_sim_time` to `true`? That will be a required step for time synchronization when using bag files.



Thomas D (May 14 '16)

Yes. I set use_sim_time to true and I am using --clock

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option while playing the rosbag.

 A G (May 15 '16)

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Typically, you use a

TimeSynchronizer for this issue.
See the [wiki](#) for details.

answered May 13 '16



mgruhler
9764 ●22 ●81 ●131
<https://github.com/mgruhler>

updated May 13 '16

[link](#)

Comments

Thanks, mig. I tried the above mentioned option. But it didn't work. Also i found a similar issue in the link mentioned below: <http://answers.ros.org/question/14635...> I even tried with approximate time policy mentioned in the above link.

 A G (May 13 '16)

An addition to the above comment: When I tried with the TimeSynchronizer and ApproximateTimePolicy method , the behavior was like the callback function was never called.

 A G (May 16 '16)

Thanks @mig! Approximate time policy mentioned in your link worked. But I have to increment the timestamp of point cloud by 5sec using a subscriber node before passing it on to the TimeSynchronizer. Otherwise the callback function has never been called!

 A G (May 18 '16)

@mig@Thomas D New issue-If I play rosbag with the **loop** option,the 1st loop will work,but during 2nd loop,callback function is not called.similar to the issue mentioned in the link <http://answers.ros.org/question/10643...> Please help me with your suggestions

 A G (May 18 '16)

can't help you there. Also, for a new issue/question, please open a new one.

 mgruhler (May 18 '16)

ok. Thanks mig!

 A G (May 18 '16)

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