



GAZEBO

About me



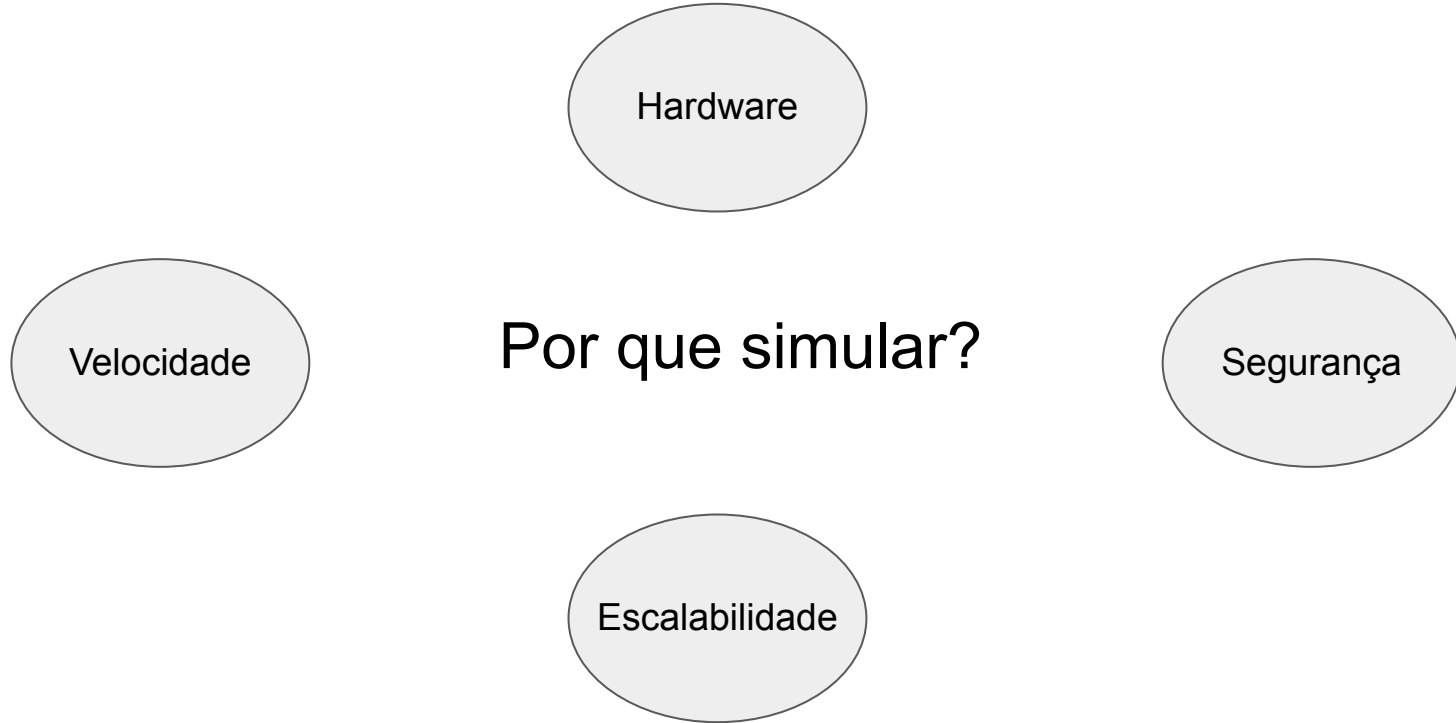
- Coordenador do time de Software da UFRJ Nautilus
- Aluno do curso de Engenharia Eletrônica e de Computação da UFRJ



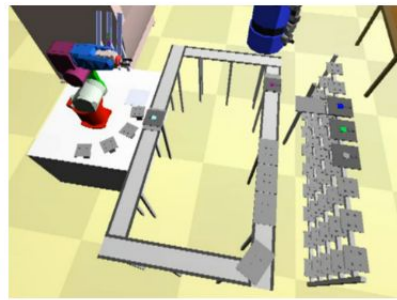
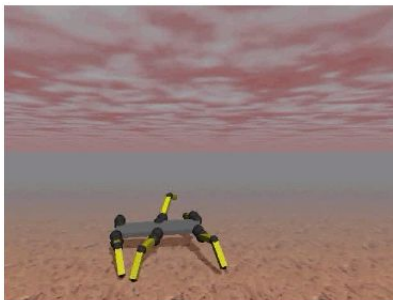
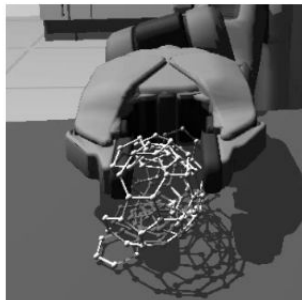
<https://github.com/matheusrod98>



<https://www.instagram.com/ufrjnautilus/>



O que podemos simular?



Modelos físicos

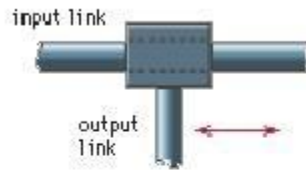


SDFormat

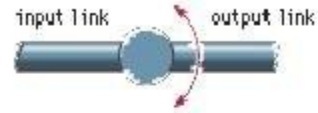
Tipos de juntas de conexão



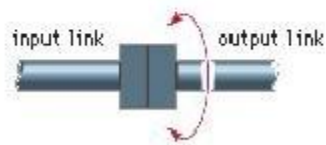
collinear joint



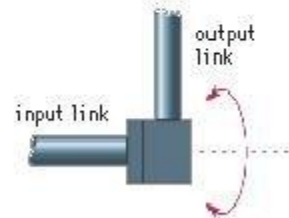
orthogonal joint



rotational joint

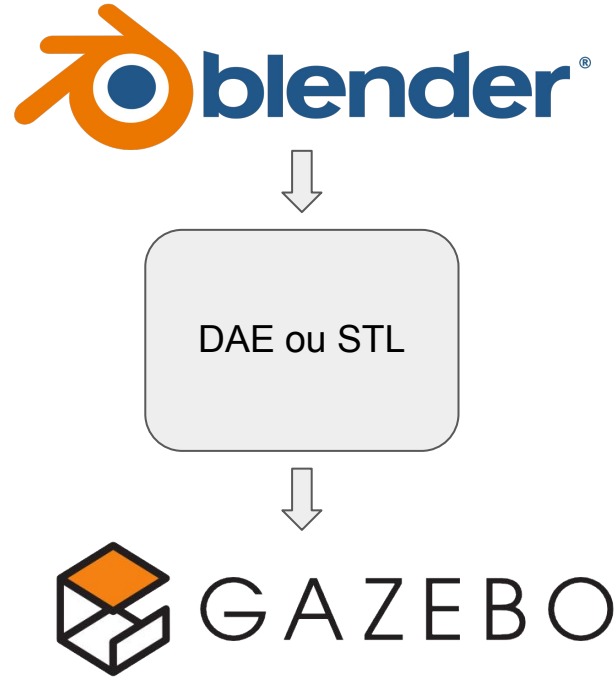


twisting joint

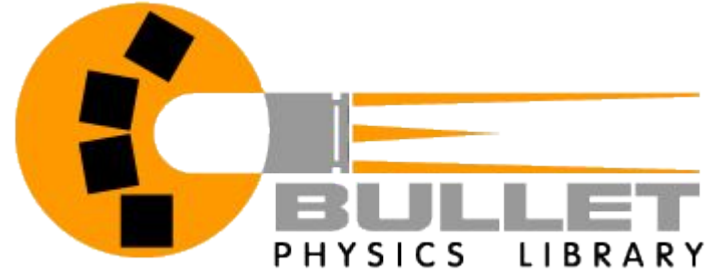


revolving joint

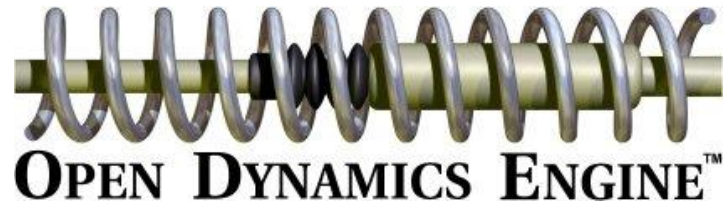
Modelos mais complexos



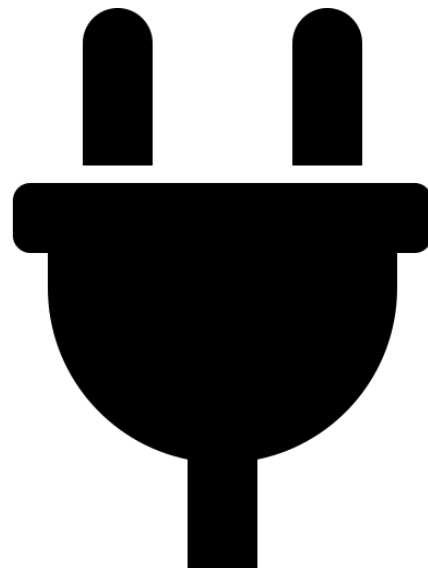
Física



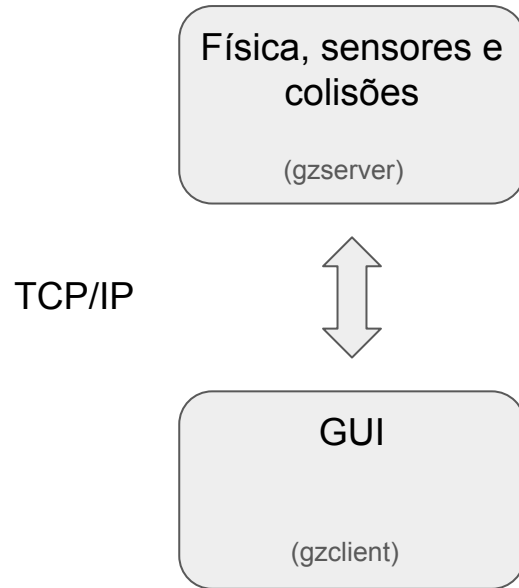
SimTK



Melhorando a simulação: Plugins



Comunicação Interna



Referências



GAZEBO

<https://docs.ros.org/en/rolling/Tutorials.html>

<https://classic.gazebosim.org/tutorials>

https://github.com/matheusrod98/gnugraf_gazebo