

```
%CVision with Kinect
```

## Initialise ROS

```
roshutdown;  
setenv('ROS_MASTER_URI','http://169.254.231.152:11311');  
setenv('ROS_IP','169.254.206.122');  
roslaunch ('http://169.254.231.152:11311/');
```

## list nodes

```
roslaunch list
```

## list topics

```
rostopic list
```

## subscribe to topics

```
imSub = rossubscriber('/camera/rgb/image_raw');  
pcSub = rossubscriber('/camera/depth/points');
```

## visualise data

```
testIm = readImage(imSub.LatestMessage);  
figure;  
imshow(testIm);
```

## create pointcloud and visualise

```
pcMsg = pcSub.LatestMessage;  
ptCloud = pointCloud(readXYZ(pcMsg));  
figure;  
pcshow(ptCloud, 'VerticalAxisDir','down');  
xlabel('X');ylabel('Y'); zlabel('Z');  
curLim = axis();  
curLim(1) = -0.5;  
curLim(2) = -0.5;  
axis(curLim);
```

## end of code