# Webcam ROS driver

1. We are going to use webcams to test the LSD SLAM algorithm. Therefore, we need a ROS driver that puts the images on a ROS topic. We will use gscam for this.

* Clone the gscam driver in your ROS workspace:  
   ***cd ~/simulation/ros\_catkin\_ws/src  
   git clone*** [***https://github.com/ros-drivers/gscam.git***](https://github.com/ros-drivers/gscam.git)
* Build the gscam ROS driver:  
   ***cd ~/simulation/ros\_catkin\_ws  
   catkin\_make --pkg gscam***
* LSD SLAM works best with an image resolution of 640x480. As we use a Full HD webcam, we have to downsample the image when we run gscam. For this purpose, go to *Code/ros\_catkin\_ws/src/gscam/launch* in this portfolio and copy the **gscam\_640\_480.launch** file to *~/simulation/ros\_catkin\_ws/src/gscam/launch*