RP LiDAR

* Overview

⇒ This package provides basic device handling for 2D Laser Scanner RPLIDAR A1/A2 & A3.

⇒ Suitable for indoor robotic slam application.

- 360 degree scan field
- 5.5hz/10hz rotating frequency
  - ↳ User can customize the scanning frequency from 2hz to 10hz freely

⇒ The driver published device-dependent Sensor_msgs/LaserScan data.

* ROS Nodes

① rplidarNode

⇒ driver for RPLIDAR

⇒ reads raw scan result using RPLIDAR's SDK and convert to ROS.

Published Topics

- ↳ scan (Sensor_msgs/LaserScan)

Services

- ↳ stop_motor (std_srvs/Empty)
  - ⇒ Call the service to stop the motor of RPLIDAR.

↳ start_motor (std_srvs/Empty)

⇒ Call the service to start the motor of rplidar.

Parameters

→ serial_port (string, default: /dev/ttyUSB0)

→ serial_baudrate (int, default: 115200)

→ frame_id (string, default: laser)

→ inverted (bool, default: false)

⇒ indicated whether the Lidar is mounted inverted.

→ angle_compensate (bool, default: true)

⇒ indicate whether the driver need do angle comp.

↳ scan_mode (string, std::string())

⇒ The scan mode of lidar.

⇒ Before running RPLIDAR driver set the permissions.

```
sudo chmod 666 /dev/ttyUSB0
```