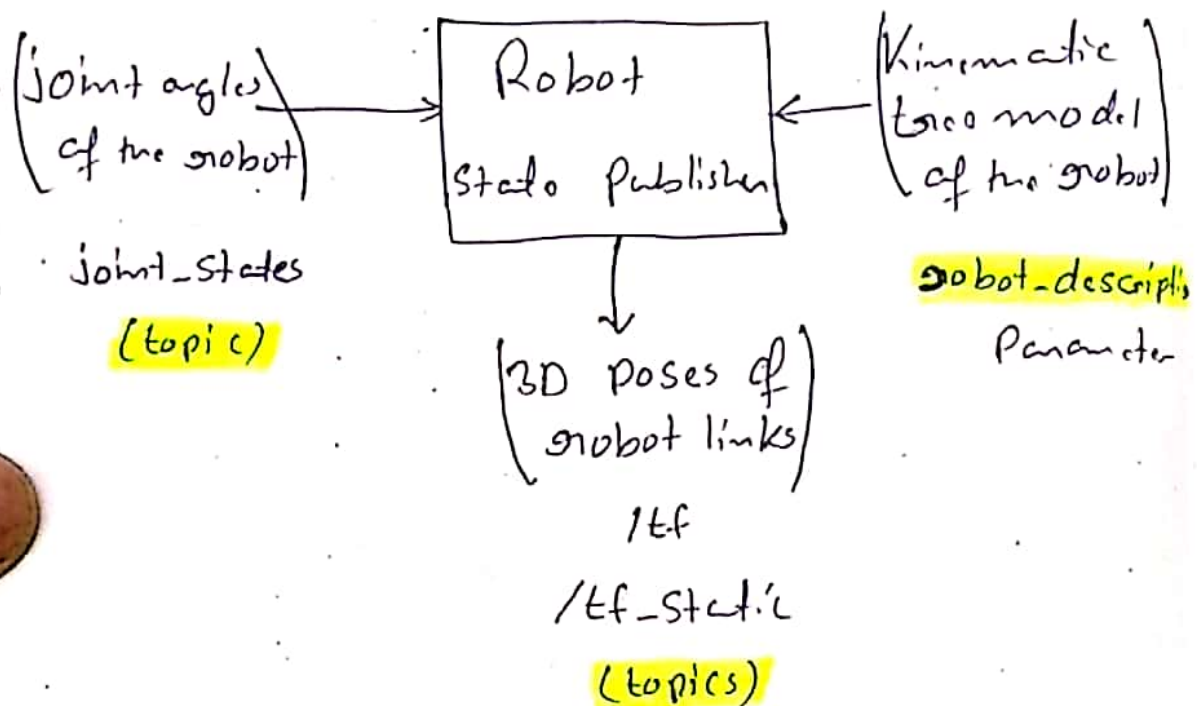# robot_state_publisher

⇒ This package allows you to publish the state of a robot to tf.

⇒ It takes joint angles of the robot as input and publish the 3D poses of the robot links using Kinematic tree model of the robot.

(Joint angles of the robot) → Robot State Publisher ← (Kinematic tree model of the robot)

· Joint_states
   (topic)

(3D poses of robot links)
   /tf
   /tf_static
   (topics)

robot_description
   Parameter

⋆ API

Subscribed topic
   ⤷ joint_states (sensor_msgs/JointState)

Parameters
   → robot_description
      (The Uridf xml robot description)

* → tf_prefix (string)

(for namespace-aware publishing
of transform.

→ publish_frequency (double)

(Publish frequency of state
publisher, default: 50Hz)

→ ignore_timestamp (bool).

(If true, ignore the publish
- frequency and time stamp
of joint_states and publish a
tf for each of the received
joint state.
Default is false)

→ Use_tf_static (bool)

(Set whether to use the /tf_static
latched static transform broadcaster
Default: true)