Display laser data with ROS

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Display laser data with ROS (1/5)

- Open 3 terminals:
  1. Roscore: *the ROS master;*
  2. Rviz: *the vizualization tool of ROS.*
     1. Put fixed frame to laser;
     2. Add LaserScan to rviz;
     3. Put the topic to /scan in LaserScan.
     4. Save your configuration file.
- See screenshots on next slides

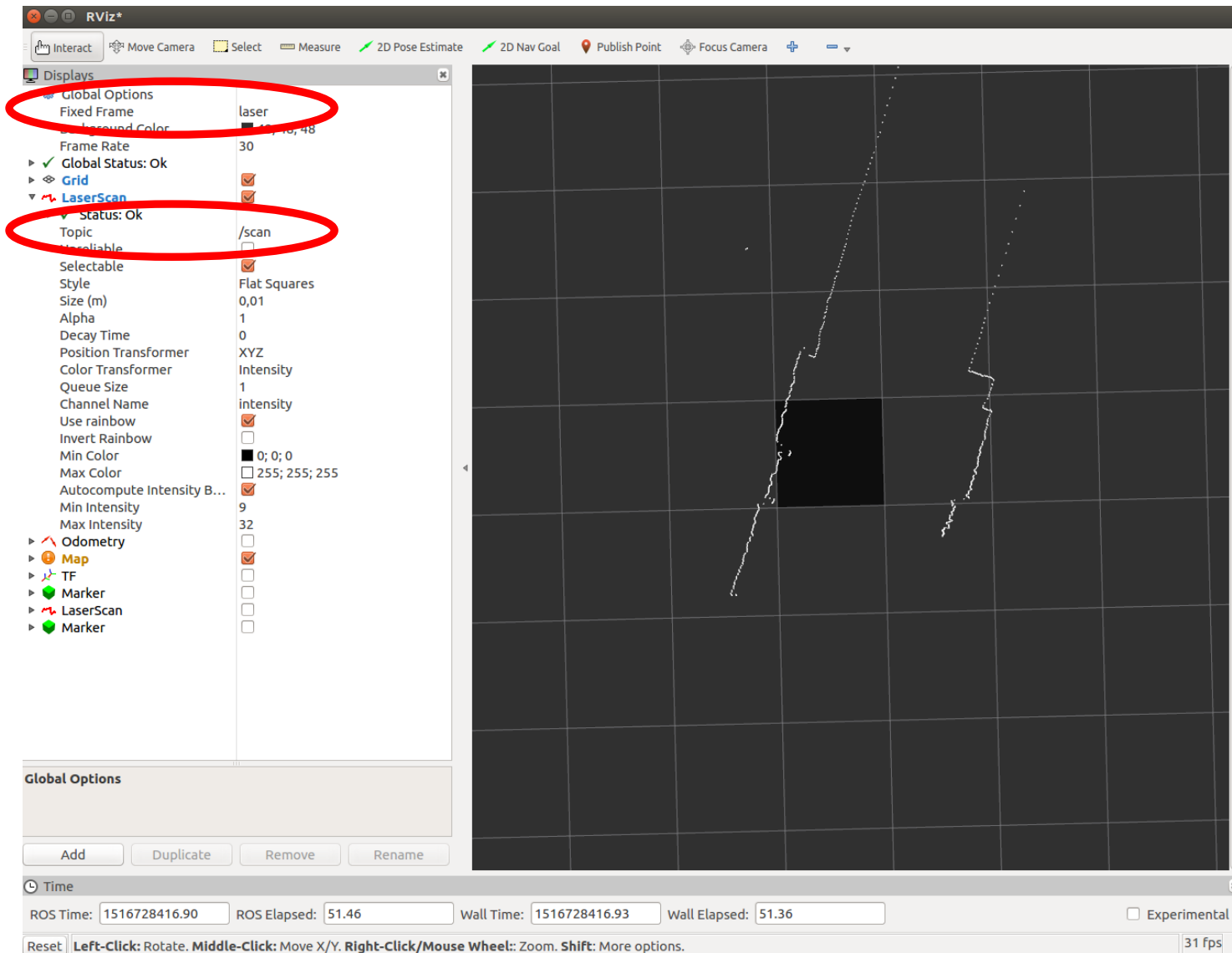*Olivier.aycard@grenoble-inp.fr*

Display laser data with ROS (2/5)

3. To play the data for detection in a third terminal
    1. Cd ~/catkin_ws/data_for_labs/datmo/detection
    2. Rosbag play *data_file*.bag: to play a saved file;
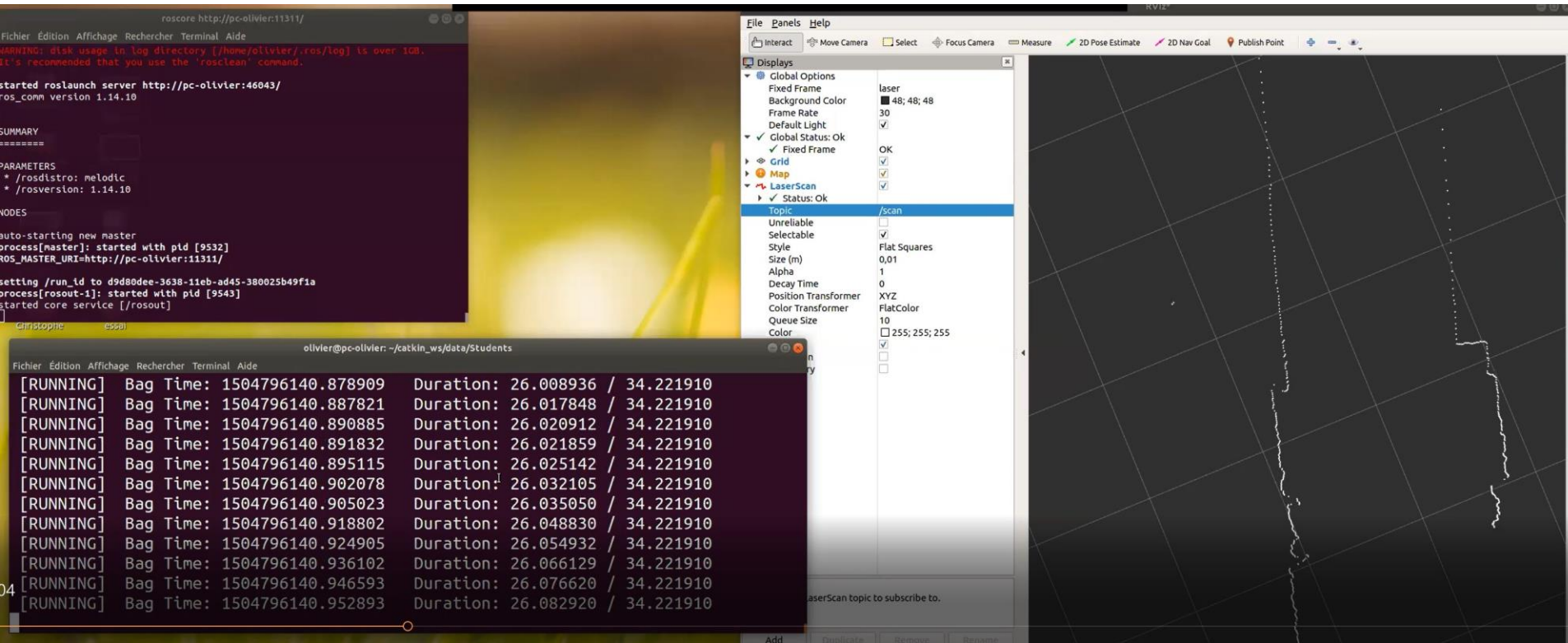   - You should choose a *data_file*.bag to play, for instance detection01.bag

Display laser data with ROS (3/5)
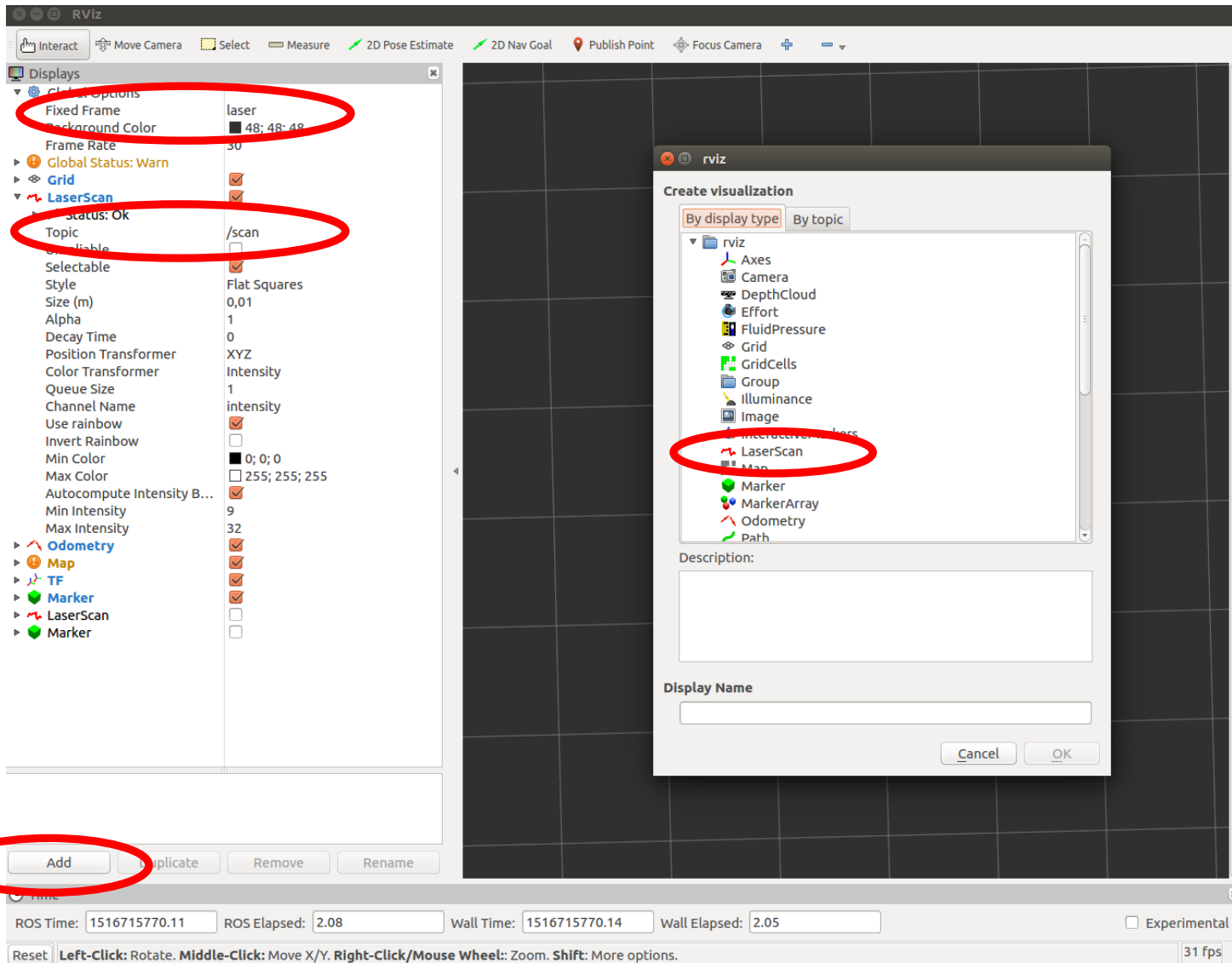
Display laser data with ROS (4/5)

Display laser data with ROS (5/5)

- To put in pause a rosbag, press space
- To run a rosbag step by step, press s

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