

# Display laser data with ROS

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# Display laser data with ROS (1/4)

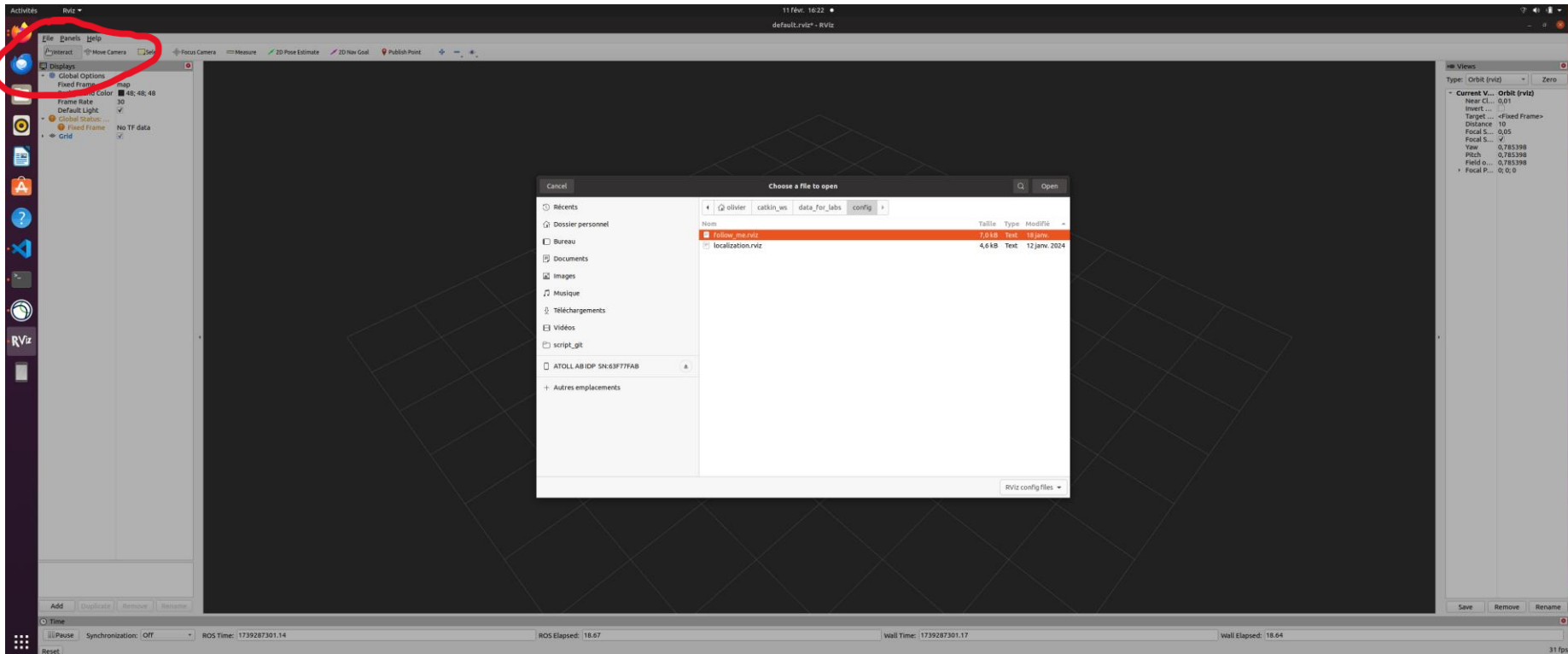
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- To download the data needed for labs on datmo:
  1. `Cd ~/catkin_ws`
  2. `\rm -r data_for_labs`
  3. `Git clone https://gricad-gitlab.univ-grenoble-alpes.fr/aycardol/data_for_labs.git`
- Open 3 tabs in a terminal:
  1. Roscore: *the ROS master*;
  2. 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`

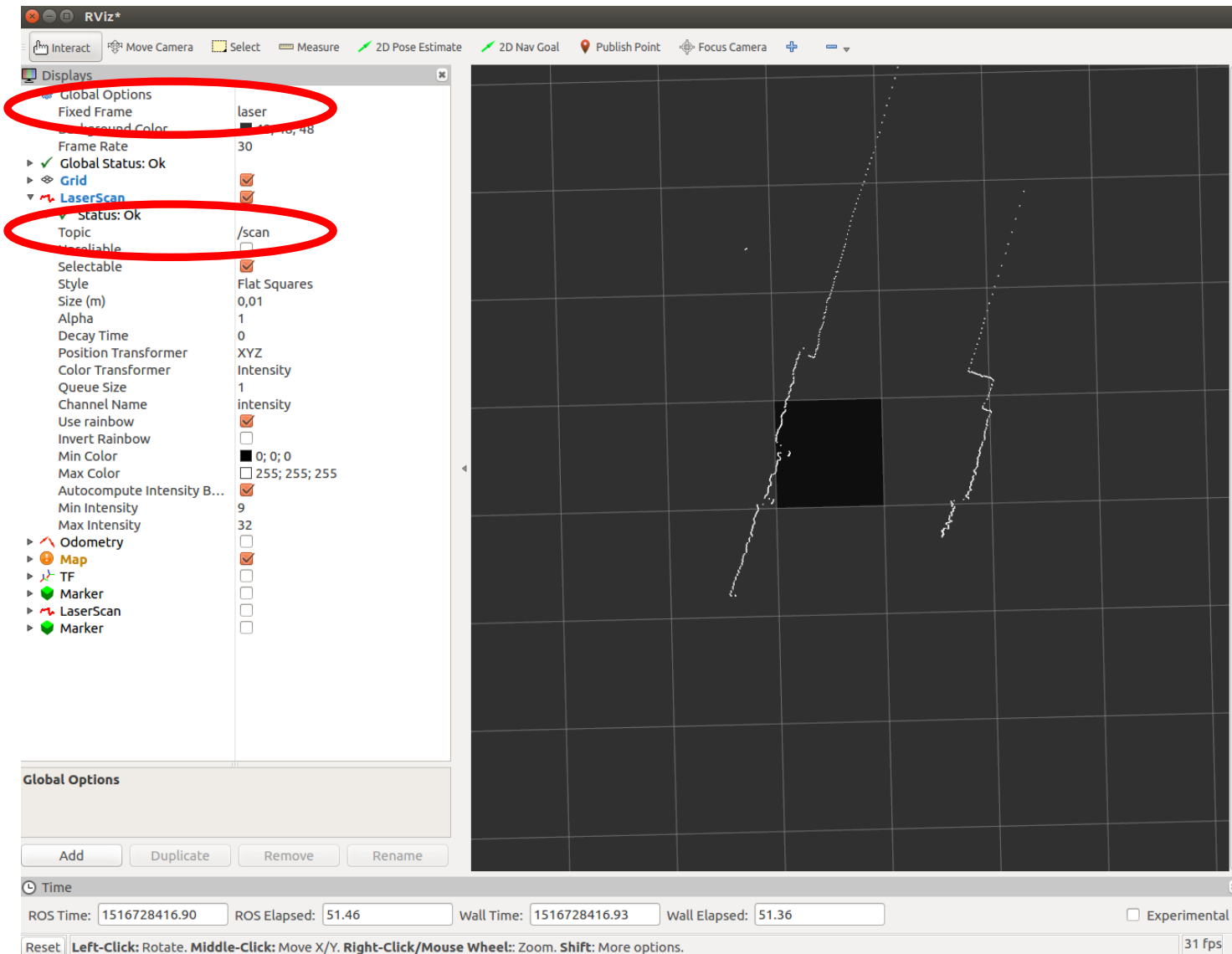
# Display laser data with ROS (2/4)

## 3. Rviz: *the vizualization tool of ROS;*

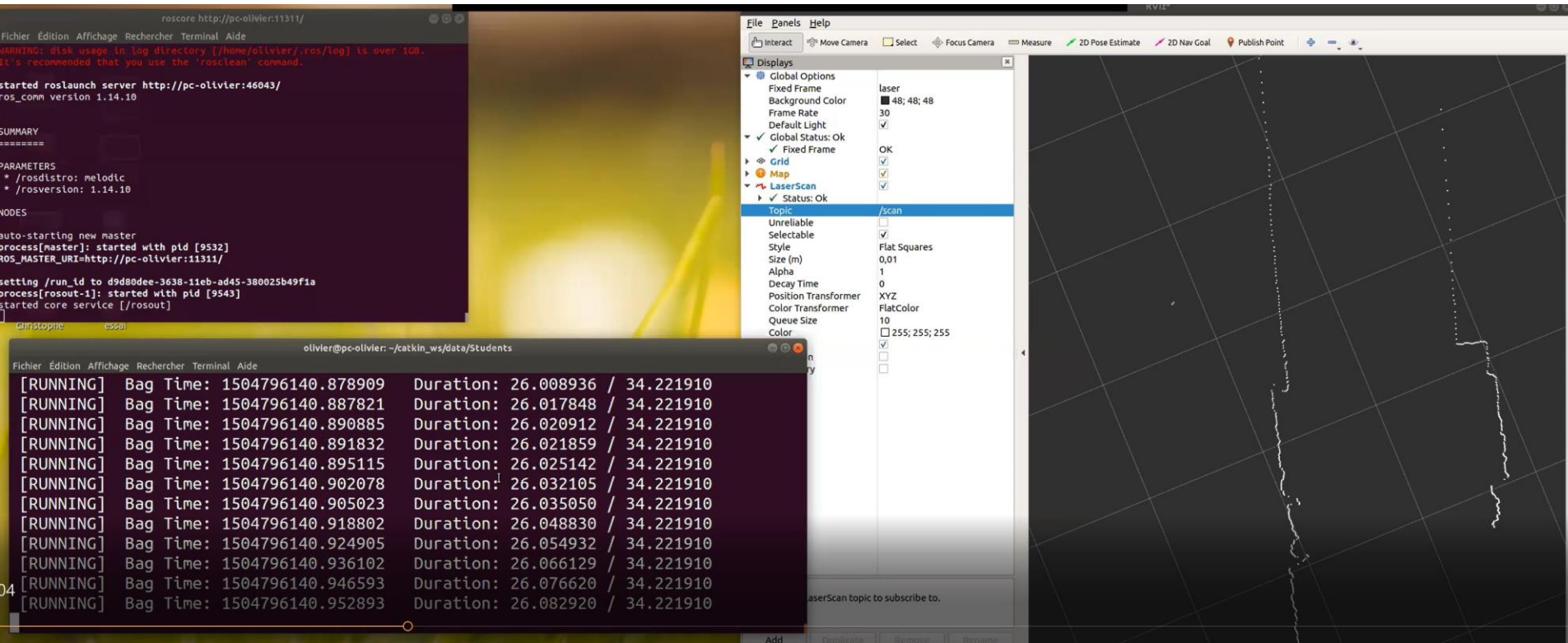
### 1. Open the configuration file



# Display laser data with ROS (3/4)



# Display laser data with ROS (4/4)



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