

ROS 理论与实践 - 作业 4

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1. launch 文件可参见./catkin_ws/src/learning_launch/launch 文件夹，运行截图如 Fig.1-Fig.3所示

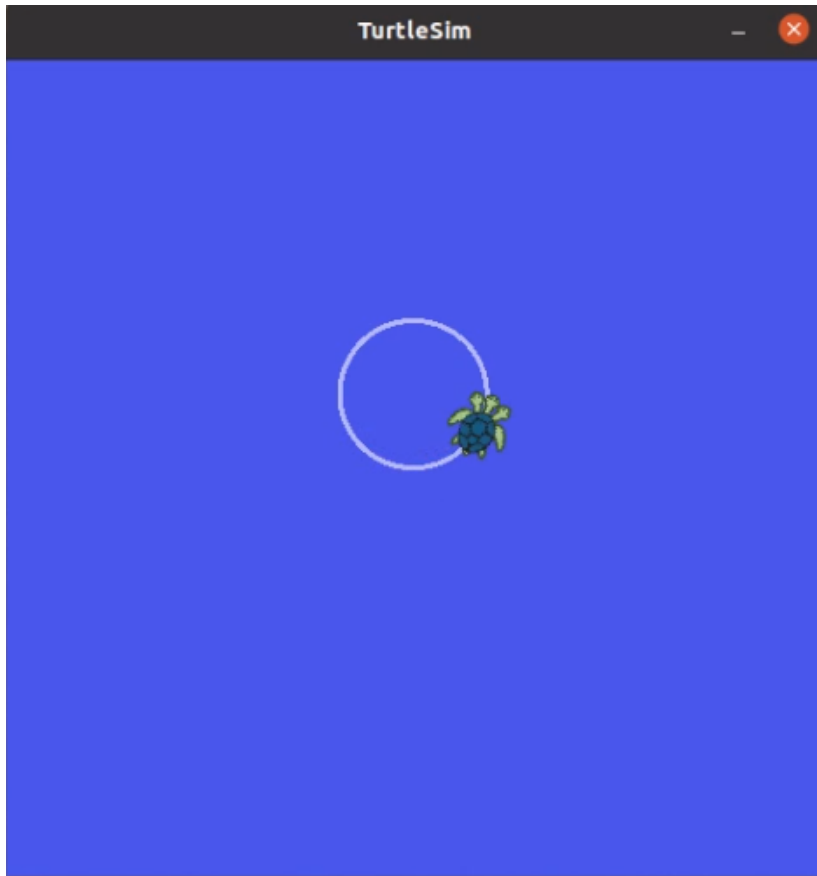


Figure 1: test1 截图

2. 在 gazebo 中添加模型后截图如 Fig.4所示
3. learning_tf 功能包运行截图如 Fig.5所示

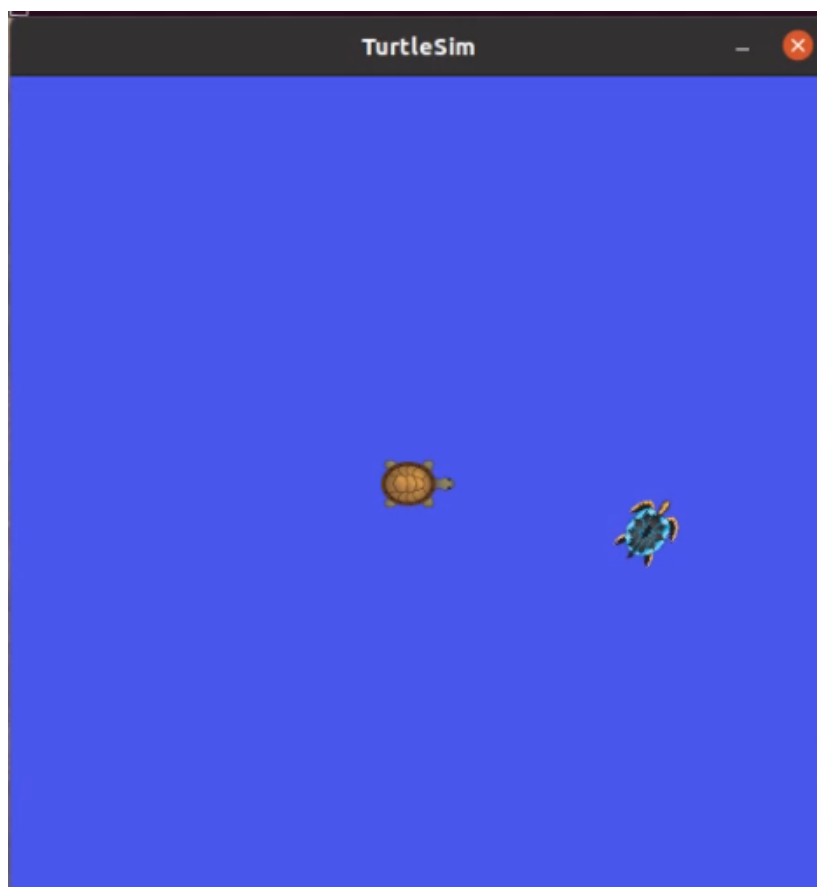


Figure 2: test2 截图

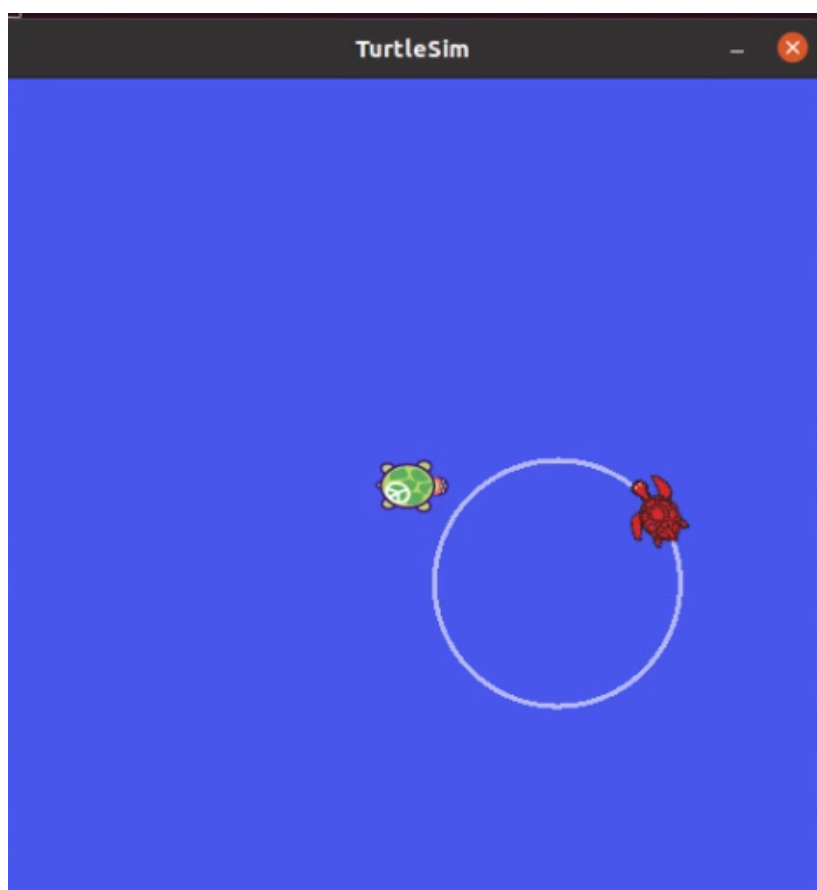


Figure 3: test3 截图

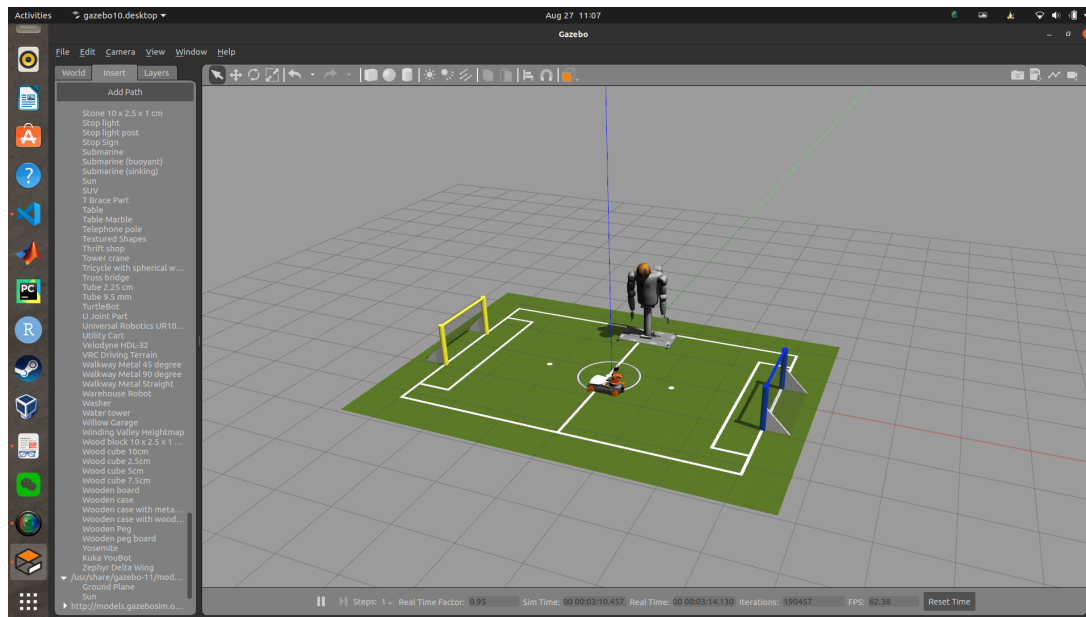


Figure 4: gazebo 截图

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/home/pengbo/ROS/assignments/hw3/catkin_ws/src/learning_...
(0.40, 0.00, 0.20) at time 1598512124.68
[ INFO] [1598512124.784479681]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512124.78
[ INFO] [1598512124.884538921]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512124.88
[ INFO] [1598512124.984452971]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512124.98
[ INFO] [1598512125.084480223]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512125.08
[ INFO] [1598512125.184486350]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512125.18
[ INFO] [1598512125.284478891]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512125.28
[ INFO] [1598512125.384562630]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512125.38
[ INFO] [1598512125.484450479]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512125.48
[ INFO] [1598512125.584447758]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512125.58
[ INFO] [1598512125.684586902]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512125.68
[ INFO] [1598512125.784423108]: base_laser: (0.30, 0.00, 0.00) -----> base_link:
(0.40, 0.00, 0.20) at time 1598512125.78

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Figure 5: learning_tf 截图