

lab8_part2

Part-2

2022-10-18

Simulation

Goal : get obstacle's point cloud and convert it to laser scan message

TO DO

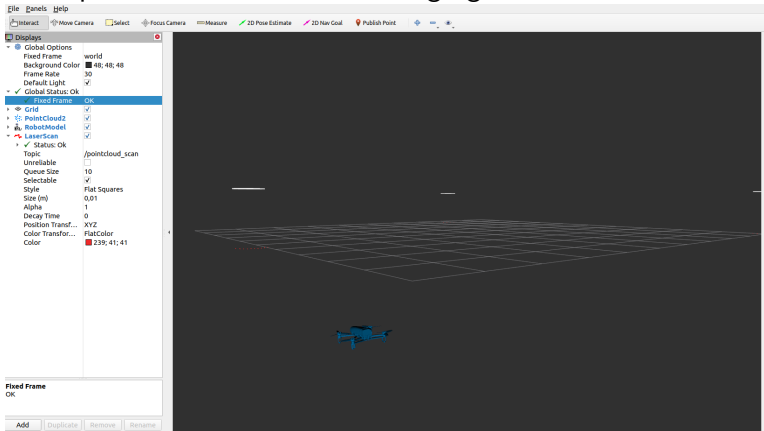
- ▶ add the following line in lab8_part1 launch file which launches the gazebo world and spawn the robot
 - ▶ `node pkg="tf" type="static_transform_publisher" name="world_to_bebop_odom" args="0 0 0 0 0 0 world odom 100" /`
- ▶ add the brackets it's missing here
- ▶ All necessary files are in lab8_part2 folder
- ▶ Use the same workspace of lab8_part1
- ▶ Do the next parts in the same package created in lab8_part1

TO DO

- ▶ create a launch file by the name of :
get_pointcloud_circular.launch . This launch file will call the the node implemented in point_cloud_circular_.py script file (provided)
- ▶ Complete The TODO's in point_cloud_circular_.py (This script subscribe to the topic publishing obstacle list , and create a point cloud)
- ▶ complete the TODO's in point_cloud_to_laser.launch launch file (This launch file convert point cloud to laser Scan message)
- ▶ include the point_cloud_to_laser.launch and get_pointcloud_circular.launch launch files in the launch file created in lab8_part1 (which launches the gazebo world and spawn the robot)

TO DO

- ▶ run rviz to visualize point cloud and laser scan messages , add the topics as shown in the following figs



TO DO

- takeoff and turn off the point cloud topic to see the laser scan messages

