

1 Inserting the Kinect camera into Husky

Short description on how to modify the Gazebo files to put Sick Laser range finder or alternatively the Kinect camera. it is sufficient to modify the husky-fabrickhalle.launch file to change the robot configuration. The **urdf** and **gazebo** files in the husky kinetic devel should remain the same.

2 Kinect camera data

Order data after in a table:

- update rate: publish a message of the sensor every N. frames specified. Eg. 200, publish the message every 200 frames, not perfectly sure with it.
- RGB image height and width
- horizontal Field of View has been placed to 90 deg to capture tags properly

3 Robot localization pkg

Some useful parameters of the package robot_localization: http://wiki.ros.org/robot_localization.