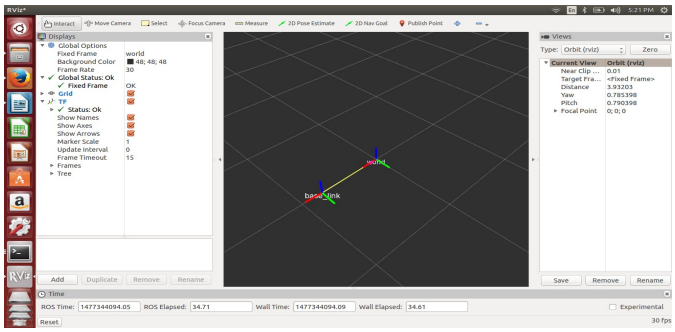
Name: Saurabh Nair (snnair) , ros part 3
Part 1:
Topics created by the ros bag
/camera/depth_registered/points_throttle
/clock
/cmd_vel
/left_motor_vel_cmd
/left_revs
/left_velocity_rps
/odom
/odom_abs
/right_cmd_echo_rps
/right_motor_vel_cmd
/right_revs
/right_velocity_rps

http://wiki.ros.org/evarobot_odometry/Tutorials/indigo/Writing%20a%20Simple%20Subscriber%20for%20Odometry
Just equated the odometric message outputs to base_link.
w not needed as motion is in 2d



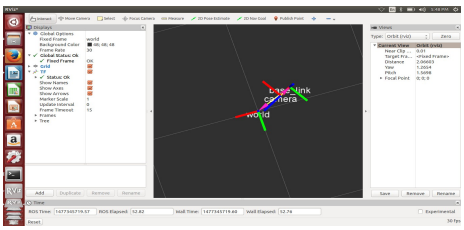
Part2:
For yaml addition referred:

http://wiki.ros.org/ROS/Tutorials/Roslaunch%20tips%20for%20larger%20projects

Did get param for rotations using previous code in the same file.

yaw pitch roll – ***quaternion***
http://docs.ros.org/api/tf/html/c++/transform__datatypes_8h.html

Added camera_frame_node node using assignment 2.



Part3:

rosbag play --clock rover_bag_part3.bag
Set in_cloud_ 's header as camera (similar to part1's code)
published *in_cloud_

In launch file, added the camera_frame node, yaml file and time parameter for time sync.
Referred :
http://wiki.ros.org/Clock
http://answers.ros.org/question/12577/when-should-i-need-clock-parameter-on-rosbag-play/
Figure of the point cloud after running q3.launch