

Thread: OgMap Resolution relating to Config Space for PRM

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**Aaron Dinoia**

15 days ago

OgMap Resolution relating to Config Space for PRM**Overall Rating:**

Hi Alen,

It's specified that "... The map resolution is specified by user, resolution is valid if it is an integer (whole number), based on the formula: $\text{pixels} = \text{map_size} / \text{resolution}$."

According to this, say we take a resolution of 10, then the number of pixels = $20 \times 20 / 10 = 40$. However if we're to create a Configuration Space then our number of rows/columns = $\text{Sqrt}[40] = 6.32$ which poses a problem. Am I approaching this correctly or have I misunderstood the specification?

Thank you!

[Reply](#)**Alen Alempijevic**

14 days ago

RE: OgMap Resolution relating to Config Space for PRM[COLLAPSE](#)**Overall Rating:**

Generally the resolution is specified by user. However for the purpose of the task and diameter of ROBOT I would state **0.1m should be fixed, consistent and throughout.**

[Reply](#)[Quote](#)[Email Author](#)[▲ Hide 2 replies](#)**Aaron Dinoia**

14 days ago

**RE: OgMap Resolution relating to Config Space for PRM****Overall Rating:**

Right, so are you saying that the number of rows and columns should be $20/0.1 = 200$?

Also, would you like us to still implement a function which allowed the user to specify the resolution?

[▲ Hide 1 reply](#)**Alen Alempijevic**

10 days ago

RE: OgMap Resolution relating to Config Space for PRM**Overall Rating:**

The user is needed can already specify the resolution when running local_map.

There is a problem of the your component finding out that resolution when it gets hold of the OpenCV Image as there is no meta-data available.

Thus, we removed this as a requirement as it is not crucial to the Assignment implementation.

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