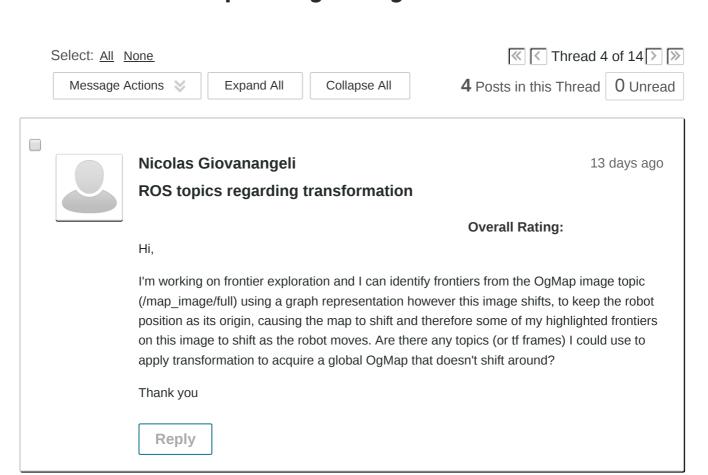
Programming for Mechatronic Systems Autumn 2017/1012-2017-AUTUMN-CITY♥

**Discussion Board** 

Forum: Assignment 5 - Individual project Thread: ROS topics regarding transformation

# Thread: ROS topics regarding transion mation







## Nicolas Giovanangeli

11 days ago

**RE:** ROS topics regarding transformation

#### **Overall Rating:**

I've addressed a bug in my code that was causing my frontiers to drift as the map image shifts to keep the local robot position at its origin, though will still welcome any guiding tips for transforming pixel coordinates of a graph into x,y coordinates

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Yujun Lai

10 days ago

**RE: ROS topics regarding transformation** 

**Overall Rating:** 

mi inicolas, vioulunt it be possible for you to clone a cv..iviat file which is your global OGMap? The representation of your robot is a pose which has a point (x,y,z) [z you can keep constant as 0] and a quaternion [which has functions allowing you convert roll pitch yaw to quaternions and back]. The transform between your current robot pose and the centre of the global OGMap would be the transform you apply to convert from your graph coords to xy relative to global OG Map. (Might be worthwhile reviewing tf\_conversions, in particular tf eigen.h; and sensor msgs::Pose) Do correct me if I am interpreting your problems incorrectly.

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Email Author

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### Nicolas Giovanangeli

10 days ago

**RE:** ROS topics regarding transformation

#### **Overall Rating:**

I'm not sure I follow, which topic contains the global map? The only published OgMap topic seems to be the "map\_image/full" which is local since the map is being moved relative to the robot. I'm having trouble linking this image to the physical map. So far conceptually I think I have to transform from the global image frame at [i,j] =[0,0] to the image center [i,j] = [rows/2,columns/2] but I get a little lost with what's been provided when converting pixels into meters [x,y] to get frontier positions relative to the robot and then from there transforming those coordinates relative to the global frame of the physical map for setting up target goal points.

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Ouote

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