

MotionPlanning 课程环境配置

我本机环境为 Windows 10 + WSL2(Ubuntu 20.04) + Ros Noetic , 使用 X11 Server 在 Windows 上显示 WSL2 的界面.

推荐使用 [MobaXterm](#) 作为终端工具, 集成了 X11 Server.

在我的环境下直接编译会报错, 需要进行以下两处修改:

```
diff --git a/CMakeLists.txt b/CMakeLists.txt
index 46ff451..18b6b6f 100755
--- a/CMakeLists.txt
+++ b/CMakeLists.txt
@@ -26,7 +26,7 @@ include_directories(
     ${PCL_INCLUDE_DIRS}
 )

-set(CMAKE_CXX_FLAGS "-std=c++11 ${CMAKE_CXX_FLAGS} -O3 -Wall") # -Wextra -
Werror
+set(CMAKE_CXX_FLAGS "-std=c++14 ${CMAKE_CXX_FLAGS} -O3 -Wall") # -Wextra -
Werror

add_executable( demo_node
    src/demo_node.cpp
diff --git a/src/demo_node.cpp b/src/demo_node.cpp
index 3f8f345..7708a42 100755
--- a/src/demo_node.cpp
+++ b/src/demo_node.cpp
@@ -104,7 +104,7 @@ void rcvPointCloudCallback(const sensor_msgs::PointCloud2
& pointcloud_map)

    pcl::toROSMsg(cloud_vis, map_vis);

-    map_vis.header.frame_id = "/world";
+    map_vis.header.frame_id = "world";
    _grid_map_vis_pub.publish(map_vis);

    _has_map = true;
```

运行截图

