YDLIDAR ROS PACKAGE V1.3.7

ROS node and test application for YDLIDAR

Visit EAI Website for more details about YDLIDAR .

How to build YDLIDAR ros package

```
1) Clone this project to your catkin's workspace src folder

--$ git clone https://github.com/yangfuyuan/ydlidar_ros

--$ cd ydlidar_ros/ydlidar_sdk

--$ git submodule init

--$ git submodule update

2) Running catkin_make to build ydlidar_node and ydlidar_client
3) Create the alias "/dev/ydlidar" for YDLIDAR

--$ roscd ydlidar/startup

--$ sudo chmod 777 ./*

--$ sudo sh initenv.sh

4) After the exceution is completed, the radar is plugged in again.
```

How to run YDLIDAR ros package

There’re two ways to run YDLIDAR ros package

1. Run YDLIDAR node and view in the rviz

```
$ roslaunch ydlidar lidar_view.launch
```

You should see YDLIDAR’s scan result in the rviz.

2. Run YDLIDAR node and view using test application

```
$ roslaunch ydlidar lidar.launch

$ rosrun ydlidar ydlidar_client
```

You should see YDLIDAR’s scan result in the console

Parameters

port (string, default: /dev/ydlidar)

```
serial port name used in your system.
```

baudrate (int, default: 115200)

```
serial port baud rate.
```

frame_id (string, default: laser_frame)

```
frame ID for the device.
```

low_exposure (low_exposure, default: false)

```
indicated whether the LIDAR has low light power mode.
```

heartbeat (bool, default: false)

```
indicated whether the LIDAR IS powered off.
```

resolution_fixed (bool, default: true)

```
indicated whether the LIDAR has a fixed angular resolution.
```

auto_reconnect (bool, default: true)

```
indicated whether the LIDAR auto reconnection.
```

reversion (bool, default: false)

```
indicated whether the LIDAR data rotation 180°.
```

intensity (bool, default: false)

```
indicated whether the LIDAR has intensity.
```

angle_min (double, default: -180)

```
Min valid angle (°) for LIDAR data.
```

angle_max (double, default: 180)

```
Max valid angle (°) for LIDAR data.
```

range_min (double, default: 0.08)

```
Min valid range (m) for LIDAR data.
```

range_max (double, default: 16.0)

```
Max valid range (m) for LIDAR data.
```

ignore_array (string, default: “”)

```
Set the current angle range value to zero.
```

samp_rate (int, default: 4)

```
the LIDAR sampling frequency.
```

frequency (double, default: 7)

```
the LIDAR scanning frequency.
```

Dependencies

1.ydlidar_sdk

Upgrade Log

2018-08-16 version:1.3.7

1.current SDK verison 1.3.7.

2.update SDK interface.

3.Check if the Lidar port setting is correct.

4.add ydldiar_sdk submodule