Plot that changes over time with incoming messages

The rxplot /accel/x:y:z plot
The rxplot /accel/x /accel/y /accel/z plot

Disparity images
The rviz graphical interface

Setting the frame_id of the marker, that is frame_marker, in the fixed frame

Setting the fixed frame to frame_pc
Two frames of each turtle are shown with respect to the /world frame.

Chapter 4, Using Sensors and Actuators with ROS

Laser sending in the data in ROS.
The rviz screen with the two-lasers contour. The green contour is the new data.

Using the depth sensor
Add a new PointCloud2 data visualization for 3D

Resolution is less than the original data
Chapter 6, Computer Vision

Configuration in Coriander
Configuration in Coriander with better exposure

RAW image of the USB camera, which is in color
Visualization of the camera images with image_view

Calibrating the camera
Calibrating the camera

The calibration process in the GUI, identical to the one with FireWire cameras.
The end of the calibration process

Stereo Calibration
Using disparity parameters, which can be set with reconfigure_gui

The left, right, and disparity images, and the reconfigure_gui interface used to configure the disparity algorithm
A map drawn in rviz

A closer view
3D reconstruction using the visual odometry

A visual odometry system running for our low-cost stereo camera
Chapter 7, Navigation Stack – Robot Setups

The Gazebo simulator showing robot properties and data

The robot moving over red arrows (grid) as you published a new tf frame transform
Chapter 8, Navigation Stack – Beyond Setups

$ roslaunch chapter8_tutorials move_base.launch

Use of initialpose
Use of `move_base_simple/goal`

A static map
A particle cloud

Robot footprint
Obstacles

Inflated obstacles
Avoiding obstacles

Sending Goals
Chapter 9, Combining Everything – Learn by Doing

The R2 in the Gazebo empty world

Controlling the R2 arms
Controlling the robot easily with interactive markers

The R2 IVA climbing legs of a real Robonaut model
The R2 on the pedestal inside of the ISS world loaded in Gazebo

The R2 with the Task Board