

ros-from-csv: publish (more or less) arbitrary csv records to a ros topic

A new convenience utility **ros-from-csv** is now available in **snark**. It reads CSV records and converts them into ROS messages with the usual conveniences of csv streams (customised fields, binary format, stream buffering/flushing, etc).

Disclaimer: **ros-from-csv** is a python application and therefore may not perform well streams that require high bandwidth or low latency.

You could try it out, using the ROS tutorial Understanding Topics (<http://wiki.ros.org/ROS/Tutorials/UnderstandingTopics>):

Run ROS Tutorial nodes:

```
> # in a new shell
> roscore
> # in a new shell
> rosrn turtlesim turtle_teleop_key
```

Send your own messages on the topic, using **ros-from-csv**:

```
> echo 1,2,3,4,5,6 | ros-from-csv /turtle1/cmd_vel
```

Or do a dry run:

```
> echo 1,2,3,4,5,6 | ros-from-csv /turtle1/cmd_vel --dry
linear:
  x: 1.0
  y: 2.0
  z: 3.0
angular:
  x: 4.0
  y: 5.0
  z: 6.0
```

You also can explicitly specify message type:

```
> # dry run
> echo 1,2,3 | ros-from-csv --type geometry_msgs.msg.Point --dry
x: 1.0
y: 2.0
z: 3.0

> # send to a topic
> echo 1,2,3 | ros-from-csv --type geometry_msgs.msg.Point some-topic
```