



## 02. Linux, ROS alapismeretek

### Elmélet

#### Linux principles



- (Was) the only OS supported by ROS
- Security
- Efficiency
- Open-source
- Community support
- User freedom
- Distributions: **Ubuntu**, Linux Mint, Debian, etc.
- Terminal usage more dominant

#### Suggestion

Install **Terminator** terminal emulator:

```
sudo apt update
sudo apt install terminator
```

## Linux commands

See some basic commands below:

- Run as administrator with `sudo`
- Manual of command `man` , e.g. `man cp`
- Package management `apt` , e.g. `apt update` , `apt install`
- Navigation `cd`
- List directory contents `ls`
- Create file `touch`
- Copy file `cp`
- Move file `mv`
- Remove file `rm`
- Make directory `mkdir`
- Remove directory `rmdir`
- Make a file executable `chmod +x <filename>`
- Safe restart: Ctrl + Alt + PrtScr + REISUB
- If not sure, just google the command

## ROS 1 → ROS 2

- ROS 2 was rewritten from scratch
- More modular architecture
- Improved support for real-time systems
- Support for multiple communication protocols
- Better interoperability with other robotic systems
- Focus on standardization and industry collaboration
- No ROS Master
- No Devel space
- `rclpy` , `rclcpp`
- More structured code ( `Node` class)

- Different build system
- Platforms: Windows, OS X, Linux

## ROS principles

### ROS workspace

#### Colcon workspace

A folder where packages are modified, built, and installed.



- Source space:
  - Source code of colcon packages
  - Space where you can extract/checkout/clone source code for the packages you want to build
- Build space
  - Colcon is invoked here to build packages
  - Colcon and CMake keep intermediate files here
- Install space:
  - Each package will be installed here; by default each package will be installed into a separate subdirectory
- Log space:
  - Contains various logging information about each colcon invocation

## ROS package principle

Enough functionality to be useful, but not too much that the package is heavyweight and difficult to use from other software.

## ROS dependencies

After cloning a new package, use the following command to install dependencies:

```
rosdep install --from-paths src --ignore-src -r -y
```

## ROS package

- Main unit to organize software in ROS
- Buildable and redistributable unit of ROS code
- Consists of (in the case of Python packages):
  - `package.xml` file containing meta information about the package
    - name
    - version
    - description
    - dependencies
    - etc.
  - `setup.py` containing instructions for how to install the package
  - `setup.cfg` is required when a package has executables, so `ros2 run` can find them
  - `/<package_name>` - a directory with the same name as your package, used by ROS 2 tools to find your package, contains `__init__.py`
  - Anything else
- `ros2 run turtlesim turtlesim_node`

## CMake

For CMake packages (C++), the package contents will be different.



## ROS node

- Executable part of ROS:
  - python scripts
  - compiled C++ code
- A process that performs computation
- Inter-node communication:
  - ROS topics (streams)
  - ROS parameter server
  - Remote Procedure Calls (RPC)
  - ROS services
  - ROS actions
- Meant to operate at a fine-grained scale
- Typically, a robot control system consists of many nodes, like:
  - Trajectory planning
  - Localization

- Read sensory data
- Process sensory data
- Motor control
- User interface
- etc.

## ROS build system---Colcon

- System for building software packages in ROS



## Environmental setup file

- setup.bash
- generated during init process of a new workspace
- extends shell environment
- ROS can find any resources that have been installed or built to that location

```
source ~/ros2_ws/install/setup.bash
```

# Gyakorlat

## 1: Turtlesim

1. Indítsuk el a `turtlesim_node`-ot és a `turtle_teleop_key` node-ot az alábbi parancsokkal, külön-külön terminál ablakokban:

```
ros2 run turtlesim turtlesim_node
```

```
ros2 run turtlesim turtle_teleop_key
```

### Tip

**Terminator**-ban `Ctrl-Shift-O` , `Ctrl-Shift-E` billentyű kombinációkkal oszthatjuk tovább az adott ablakot. `Ctrl-Shift-W` bezárja az aktív ablakot.

### Futtatás megszakítása

`Ctrl-C`

2. Az alábbi ROS parancsok futtatása hasznos információkkal szolgálhat:

```
ros2 wtf  
ros2 node list  
ros2 node info /turtlesim  
ros2 topic list  
ros2 topic info /turtle1/cmd_vel  
ros2 interface show geometry_msgs/msg/Twist  
ros2 topic echo /turtle1/cmd_vel
```

3. Az alábbi paranccsal indítsuk el az `rqt_gui` -t:

```
ros2 run rqt_gui rqt_gui
```

4. Jelenítsük meg a futó node-okat és topic-okat `rqt_gui` -ban: Plugins → Introspection → Node Graph.



5. Publikáljunk a `/turtle1/cmd_vel` topic-ba szintén az `rqt_gui` felhasználásával:  
Plugins → Topics → Message Publisher.



## 2: ROS 2 workspace létrehozása

1. Hozzunk létre új ROS2 workspace-t `ros2_ws` névvel.

```
mkdir -p ~/ros2_ws/src
```

## 3: ROS 2 package létrehozása

1. Hozzunk létre új ROS2 package-et `ros2_course` névvel és egy Hello World-del.

```
cd ~/ros2_ws/src  
ros2 pkg create --build-type ament_python --node-name hello ros2_course
```

## Szintaxis

```
ros2 pkg create --build-type ament_python <package_name>
```

### 2. Build-eljük a workspace-t.

```
cd ~/ros2_ws  
colcon build --symlink-install
```

## Symlink

A `--symlink-install` opció az Install space-be belinkeli a forrás script-eket, így módosítás után nem kell újra build-elünk.

### 3. A `~/bashrc` fájl végére illesszük be az alábbi sort:

```
source ~/ros2_ws/install/setup.bash
```

## Importálás QtCreator-ba

New file or project → Other project → ROS Workspace. Válasszuk ki a Colcon-t, mint Build System, és a `ros2_ws`-t, mint Worksapce path.

## Importálás CLion-ba

Állítsuk be a Python interpretert Python 3.8-ra, `/usr/bin/python3`. Adjuk hozzá akövetkező elérési utat: `/opt/ros/foxy/lib/python3.8/site-packages`. Hozzuk létre a `compile_commands.json` fájlt a `~/ros2_ws/build` könyvtárban az alábbi tartalommal:

```
[  
]
```

### 4. Teszteljük a Hello World működését:

```
ros2 run ros2_course hello
```

## 4: Publisher implementálása Python-ban

1. Navigáljunk a `ros2_ws/src/ros2_course/ros2_course` mappába és hozzuk létre a `talker.py` fájlt az alábbi tartalommal.

```
import rclpy
from rclpy.node import Node

from std_msgs.msg import String

class MinimalPublisher(Node):

    def __init__(self):
        super().__init__('minimal_publisher')
        self.publisher_ = self.create_publisher(String, 'chatter', 10)
        timer_period = 0.5 # seconds
        self.timer = self.create_timer(timer_period, self.timer_callback)
        self.i = 0

    def timer_callback(self):
        msg = String()
        msg.data = 'Hello World: %d' % self.i
        self.publisher_.publish(msg)
        self.get_logger().info('Publishing: "%s"' % msg.data)
        self.i += 1

def main(args=None):
    rclpy.init(args=args)
    minimal_publisher = MinimalPublisher()
    rclpy.spin(minimal_publisher)

    # Destroy the node explicitly
    # (optional - otherwise it will be done automatically
    # when the garbage collector destroys the node object)
    minimal_publisher.destroy_node()
    rclpy.shutdown()

if __name__ == '__main__':
    main()
```

2. A `setup.py` fájlban adjunk meg egy új entry point-on:

```
'talker = ros2_course.talker:main',
```

3. Build-eljük és futtassuk a node-ot:

```
cd ~/ros2_ws
colcon build --symlink-install
ros2 run ros2_course talker
```

4. Ellenőrizzük le a node kimenetét a `ros2 topic echo` parancs vagy az `rqt_gui` használatával.

## 5: Subscriber implementálása Python-ban

1. Navigáljunk a `ros2_ws/src/ros2_course/ros2_course` mappába és hozzuk létre a `listener.py` fájlt az alábbi tartalommal.

```
import rclpy
from rclpy.node import Node
from std_msgs.msg import String

class MinimalSubscriber(Node):

    def __init__(self):
        super().__init__('minimal_subscriber')
        self.subscription = self.create_subscription(
            String,
            'chatter',
            self.listener_callback,
            10)
        self.subscription # prevent unused variable warning

    def listener_callback(self, msg):
        self.get_logger().info('I heard msg: "%s"' % msg.data)

def main(args=None):
    rclpy.init(args=args)
    minimal_subscriber = MinimalSubscriber()
    rclpy.spin(minimal_subscriber)

    # Destroy the node explicitly
    # (optional - otherwise it will be done automatically
    # when the garbage collector destroys the node object)
    minimal_subscriber.destroy_node()
    rclpy.shutdown()

if __name__ == '__main__':
    main()
```

2. A `setup.py` fájlban adjunk meg egy új entry point-on:

```
'listener = ros2_course.listener:main',
```

3. Build-eljük és futtassuk mind a 2 node-ot:

```
cd ~/ros2_ws  
colcon build --symlink-install  
ros2 run ros2_course talker
```

```
ros2 run ros2_course listener
```

4. Az `rqt_gui` használatával jeleníttessük meg a futó rendszer node-jait és topic-jait:

```
ros2 run rqt_gui rqt_gui
```

## Hasznos linkek

- [ROS 2 Tutorials](#)
- [What is a ROS 2 package?](#)