02. Linux, ROS alapismeretek

Elmélet

Linux principles



- (Was) the only OS supported by ROS
- Security
- Efficieny
- 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: Crtl + Alt + PrtScr + REISUB
- If not sure, just google the command

$ROS 1 \rightarrow ROS 2$

- 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

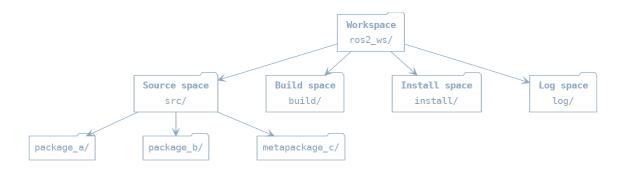
ROS principles

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 depenencies:

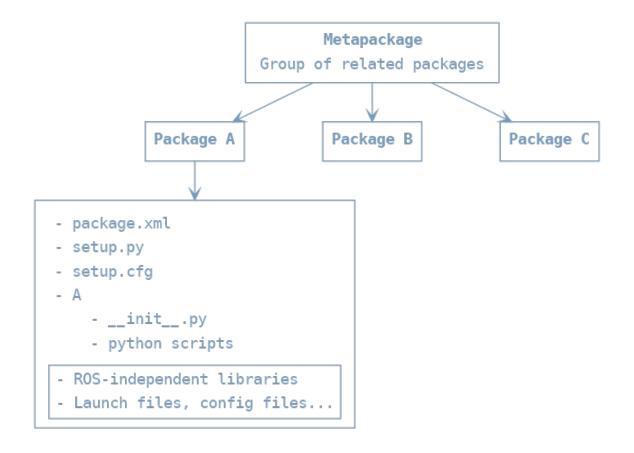
rosdep install --from-paths src --ignore-src -r -y

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.



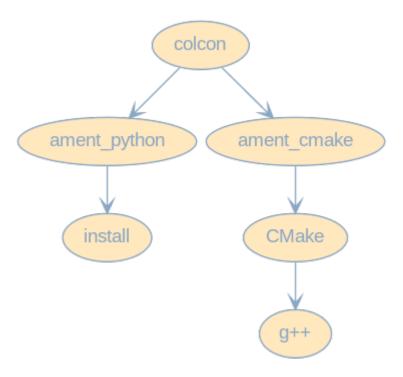
ROS node

- 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, külö-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:

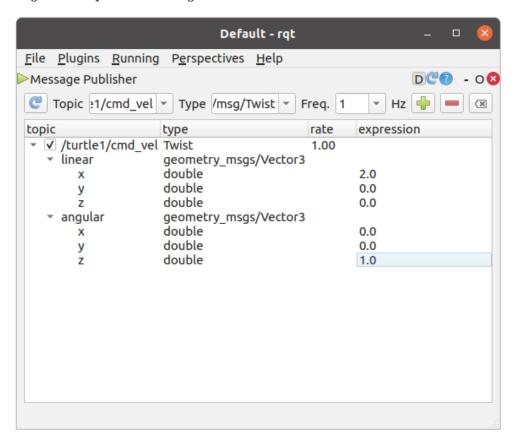
ros2 wtf
ros2 node list
ros2 node info /turtlesim
ros2 topic list
ros2 topic info /turtle1/cmd_vel
ros2 interface show geometry_msgs/msg/Twist
ros2 topic echo /turtle1/cmd_vel

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
```



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-elnünk.

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

source ~/ros2_ws/install/setup.bash

Importálás QtCreator-ba

New file or project \rightarrow Other project \rightarrow 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)
  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,
    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()
```

 $_{2.}\,^{\mathrm{A}}\,$ setup.py fájlban adjunk meg egy új entry point-on:

```
'listener = ros3_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?