

# Handle control

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## Handle control

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jetson nano  
Raspberry Pi

## 1、Operating environment

Operating system: Ubuntu 18.04 LTS

ROS version: melodic

Device: jetson nano 、Raspberry Pi、PC、handle (USB receiver)

Handle control function package path: ~/transbot\_ws/src/transbot\_ctrl

## 2、Install driver

ROS driver for general Linux handles. The Joy package contains Joy\_node, which is a node that connects a general Linux controller to ROS. The node publishes a "/Joy" message, which contains the current state of each button and axis of the handle.

```
sudo apt install ros-melodic-joy ros-melodic-joystick-drivers
```

## 3、Steps for usage

- Device connection

First of all, we need to insert the USB adapter of the wireless controller into Jetson NANO, Raspberry Pi, and PC.

In this lesson, we will insert the USB port of the wireless controller to Jetson NANO board.

- View device

Open the terminal, enter the following command, it shows [js0], this is the wireless controller.

```
ls /dev/input
```

```
jetson@jetson-yahboom: ~  
jetson@jetson-yahboom:~$ ls /dev/input  
by-id by-path event0 event1 event2 event3 event4 event5 event6 event7 js0 nice mouse0  
jetson@jetson-yahboom:~$
```

- Test handle

Open the terminal and input the following commands.

As shown in the figure, the wireless handle has 8 axial inputs and 15 key inputs. You can press the keys to test the numbers corresponding to the keys on handle.

```
sudo jstest /dev/input/js0
```

```
jetson@jetson-yahboom:~$ sudo jstest /dev/input/js0  
Driver version is 2.1.0.  
Joystick (IGZ Controller) has 8 axes (X, Y, Z, Rz, Gas, Brake, Hat0X, Hat0Y)  
and 15 buttons (BtnA, BtnB, BtnC, BtnX, BtnY, BtnZ, BtnL, BtnR, BtnL2, BtnR2, BtnSelect, BtnStart, BtnMode, BtnThumbL, BtnThumbR).  
Testing ... (interrupt to exit)  
Axes: 0:-32767 1:-32767 2:-32767 3:-32767 4:-32767 5:-32767 6: 0 7: 0 Buttons: 0:off 1:off 2:off 3:off 4:off 5:off 6:off 7:off 8:off 9:off 10:off 11:off 12:off 13:off 14:off
```

If jstest is not installed, you need run the following command to install it.

```
sudo apt-get install joystick
```

- Run the controller node

Open three terminals, enter the following commands in sequence to view the detailed information, which is the same as [Test Handle].

Different devices (Raspberry Pi, Jetson NANO, PC) and different systems have different handle states.

```
roscore Step.1  
roslaunch joy joy_node Step.3  
rostopic echo joy Step.3
```

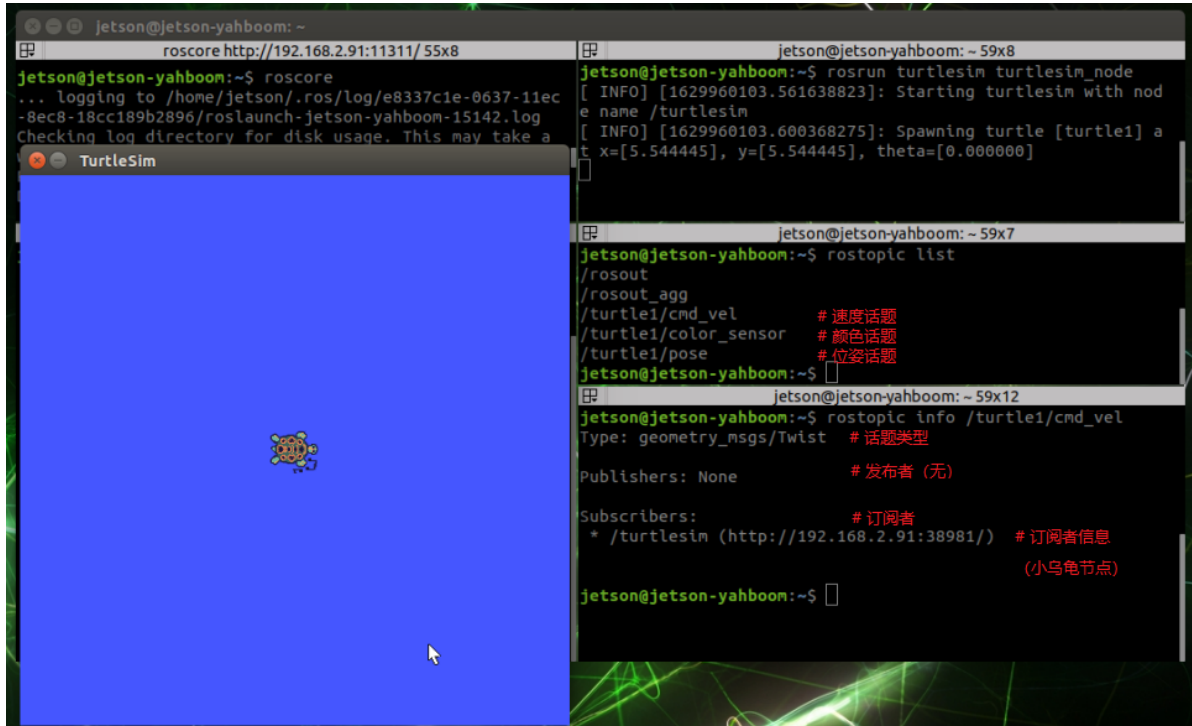
```
jetson@jetson-yahboom: ~  
roscore http://192.168.2.91:11311/66x16  
jetson@jetson-yahboom:~$ roscore  
... logging to /home/jetson/.ros/log/8a117abe-0637-11ec-a654-18cc1  
89b2896/roslaunch-jetson-yahboom-2218.log  
Checking log directory for disk usage. This may take a while.  
Press Ctrl-C to interrupt  
Done checking log file disk usage. Usage is <1GB.  
started roslaunch server http://192.168.2.91:35151/  
ros_comm version 1.14.11  
  
SUMMARY  
-----  
PARAMETERS  
* /roscore: melodic  
  
jetson@jetson-yahboom:~$ roslaunch joy joy_node  
[ WARN] [1629959656.647290938]: Couldn't set gain on joystick force  
feedback: Bad file descriptor  
[ INFO] [1629959656.657392553]: Opened joystick: /dev/input/js0. d  
eadzone_: 0.050000.  
  
jetson@jetson-yahboom:~$ rostopic echo joy  
header:  
seq: 1  
stamp:  
secs: 1629959689  
nsecs: 128446026  
frame_id: "/dev/input/js0"  
axes: [0.0, 0.0, 0.0, 0.2186940312385559, 0.0, 0.0, 0.0, 0.0]  
buttons: [0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0]  
---  
header:  
seq: 2  
stamp:  
secs: 1629959689  
nsecs: 128423930  
frame_id: "/dev/input/js0"  
axes: [0.0, 0.0, 0.0, 0.6636217832565308, 0.0, 0.0, 0.0, 0.0]  
buttons: [0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0]  
---  
header:  
seq: 3  
stamp:  
secs: 1629959689  
nsecs: 144449487  
frame_id: "/dev/input/js0"  
axes: [0.0, 0.0, 0.0, 0.8915147185325623, 0.0, 0.0, 0.0, 0.0]  
buttons: [0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0]  
---  
header:  
seq: 4  
stamp:  
secs: 1629959689  
nsecs: 152497037  
frame_id: "/dev/input/js0"
```

## 4、Handle control turtle

### 4.1、Start the turtle

```
roscore
roslaunch turtlesim turtlesim_node
```

If you want to drive the little turtle, just give the little turtle a certain speed. Next, check the ROS speed control node.



### 4.2、View node

```
rostopic list
```

### 4.3、View the node information

```
rostopic info /turtle1/cmd_vel
```

### 4.4、Handle control turtle

Receive the current status information of the handle, and send instructions to the little turtle by pressing the button or shaking the joystick to receive different information feedback from the wireless handle.

Copy the wireless controller control function package to the workspace, compile and update the environment.

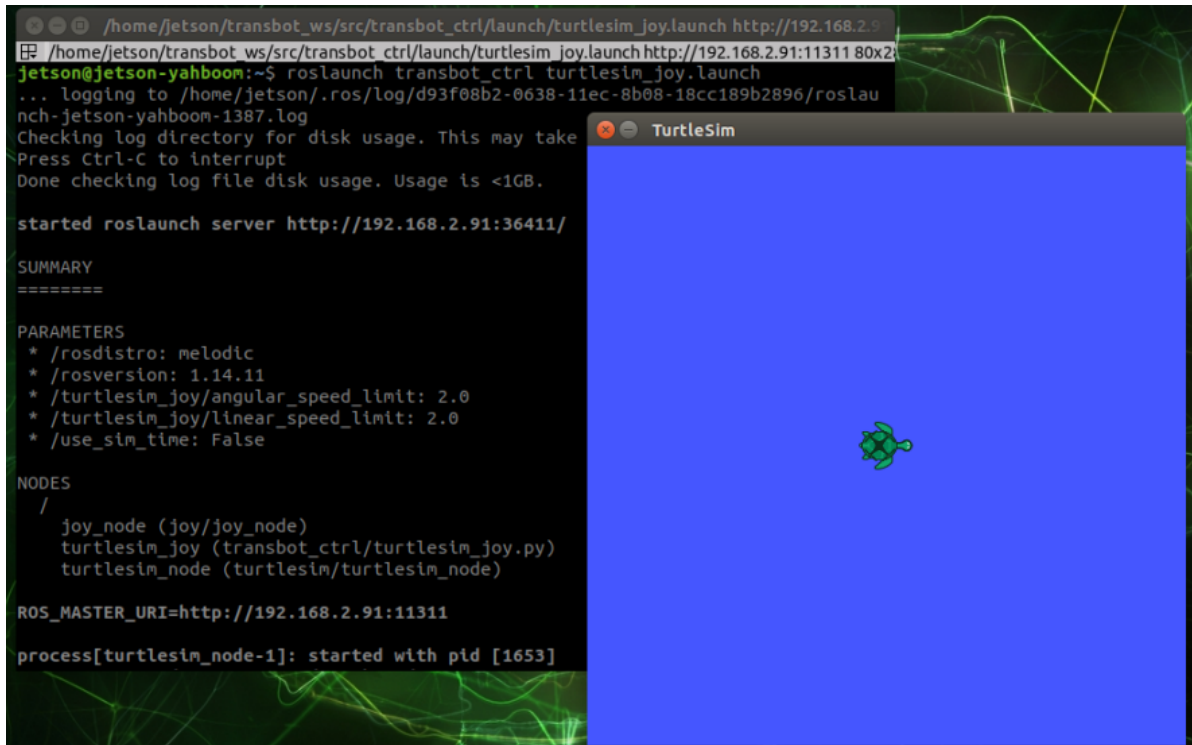
```
catkin_make # Compile
source devel/setup.bash # Update environment
Note: As long as you modify the C++ code, you must recompile the update to take effect.
```

Input command to start up python code

```
roslaunch transbot_ctrl turtlesim_joy.launch
```

Input command to start up C++ code

```
roslaunch transbot_ctrl turtlesim_turtle.launch
```



At this point, we can use the handle to control the little turtle to run.

- Correspondence between the handle and the turtle

Handle	Turtle
Left rocker up	advance
Left rocker down	back
Left rocker left	turn left
Left rocker right	turn right

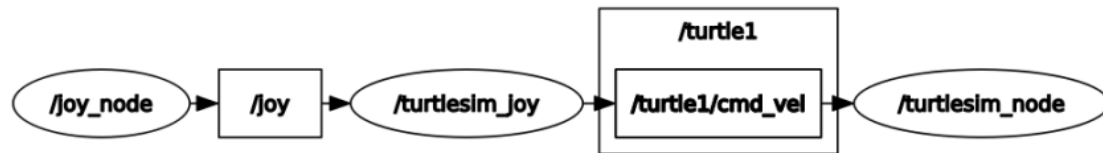
- View node graph

【/joy\_node】 : Handle information node

【/turtlesim\_joy】 : Handle control node

【/turtlesim\_node】 : Turtle node

```
rqt_graph
```



## 5、Handle control Transbot

Handle controls Transbot, which is similar to the handle control of the turtle; let the handle control node establish a connection with the Transbot bottom driver node, change the current state of the handle, send different information to Transbot, and drive Transbot to make different responses. We need to control the buzzer, searchlight, pan-tilt, light bar, robotic arm, and trolley movement (linear velocity, angular velocity).

### 5.1、handle control node

- Corresponding to the MCU coprocessor of Transbot
  - Topic
    - Publish car movement news 【/cmd\_vel】
    - Publish robotic arm control message 【/TargetAngle】
    - Publish gimbal servo control message 【/PWMServo】
  - Service (client)
    - Publish buzzer control message 【/Buzzer】
    - Publish searchlight control message 【/Headlight】
    - Publish obtain the current angle of the robotic arm 【/CurrentAngle】
    - Publish running water light control message 【/RGBLight】
- Other topic
  - Joy\_node corresponds
    - Subscribe to the news of the wireless controller 【/joy】
  - corresponding to move\_base
    - Issue the cancel motion planning message 【/move\_base/cancel】
  - Pause/start of all functions
    - Publish the current Joy state (custom) message 【/JoyState】
  - Node 【DeviceSrv】
    - Get the current camera device 【/CamDevice】

### 5.2、Associated node

- Low-level driver
  - Topic
    - Subscribe to car sports messages 【/cmd\_vel】
    - Subscribe to robotic arm control messages 【/TargetAngle】

Subscribe to gimbal servo control messages 【/PWMServo】

- Service (client)

Publish buzzer control message 【/Buzzer】

Publish searchlight control message 【/Headlight】

Publish obtain the current angle of the robotic arm 【/CurrentAngle】

Publish running water light control message 【/RGBLight】

- Joy\_node

- Topic

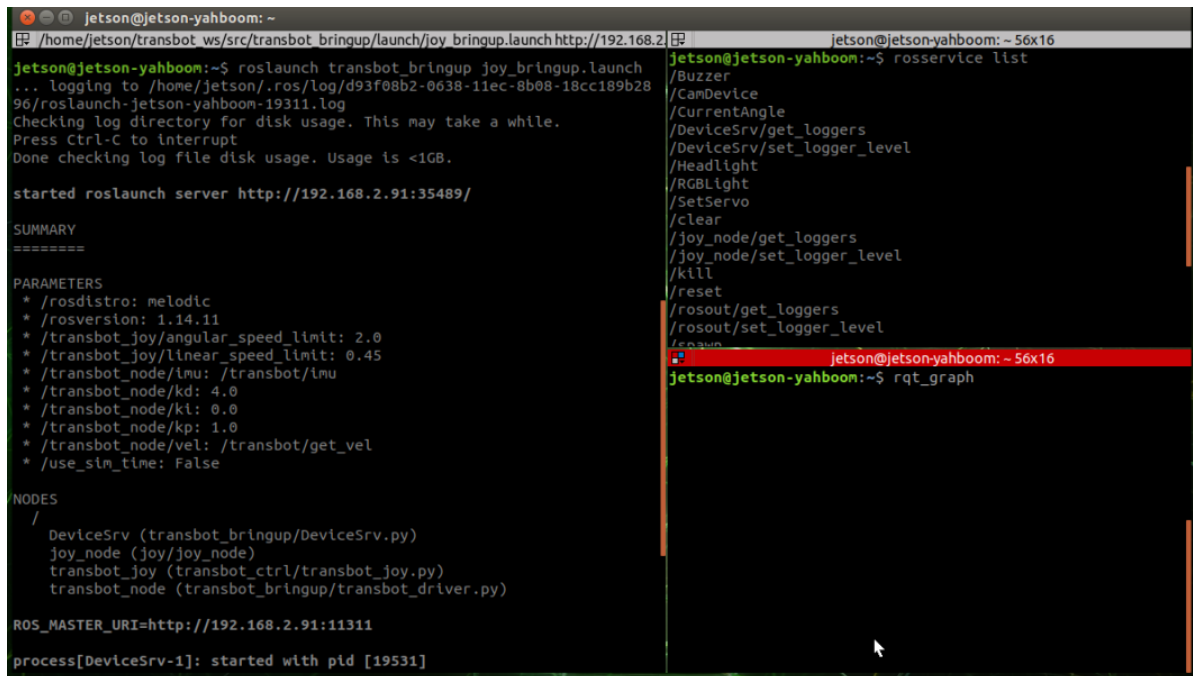
Publish the news of the wireless controller 【/joy】

- DeviceSrv

- service

Enable access to the current camera equipment service 【/CamDevice】

### 5.3、Operating procedures



The screenshot shows a terminal window with two panes. The left pane shows the execution of `roslaunch transbot_bringup joy_bringup.launch`, which logs the process and lists parameters and nodes. The right pane shows the output of `rosservice list`, listing various services available in the ROS environment.

```
jetson@jetson-yahboom: ~  
/home/jetson/transbot_ws/src/transbot_bringup/launch/joy_bringup.launch http://192.168.2.91:11311  
jetson@jetson-yahboom: ~ 56x16  
jetson@jetson-yahboom:~$ roslaunch transbot_bringup joy_bringup.launch  
... logging to /home/jetson/.ros/log/d93f08b2-0638-11ec-8b08-18cc189b28  
96/roslaunch-jetson-yahboom-19311.log  
Checking log directory for disk usage. This may take a while.  
Press Ctrl-C to interrupt  
Done checking log file disk usage. Usage is <1GB.  
  
started roslaunch server http://192.168.2.91:35489/  
  
SUMMARY  
=====  
  
PARAMETERS  
* /rostdistro: melodic  
* /rosversion: 1.14.11  
* /transbot_joy/angular_speed_limit: 2.0  
* /transbot_joy/linear_speed_limit: 0.45  
* /transbot_node/imu: /transbot/imu  
* /transbot_node/kd: 4.0  
* /transbot_node/ki: 0.0  
* /transbot_node/kp: 1.0  
* /transbot_node/vel: /transbot/get_vel  
* /use_sim_time: False  
  
NODES  
/  
  DeviceSrv (transbot_bringup/DeviceSrv.py)  
  joy_node (joy/joy_node)  
  transbot_joy (transbot_ctrl/transbot_joy.py)  
  transbot_node (transbot_bringup/transbot_driver.py)  
  
ROS_MASTER_URI=http://192.168.2.91:11311  
  
process[DeviceSrv-1]: started with pid [19531]  
  
jetson@jetson-yahboom:~$ rosservice list  
/Buzzer  
/CamDevice  
/CurrentAngle  
/DeviceSrv/get_loggers  
/DeviceSrv/set_logger_level  
/Headlight  
/RGBLight  
/SetServo  
/clear  
/joy_node/get_loggers  
/joy_node/set_logger_level  
/kill  
/reset  
/rosout/get_loggers  
/rosout/set_logger_level  
/spawn  
jetson@jetson-yahboom: ~ 56x16  
jetson@jetson-yahboom:~$ rqt_graph
```

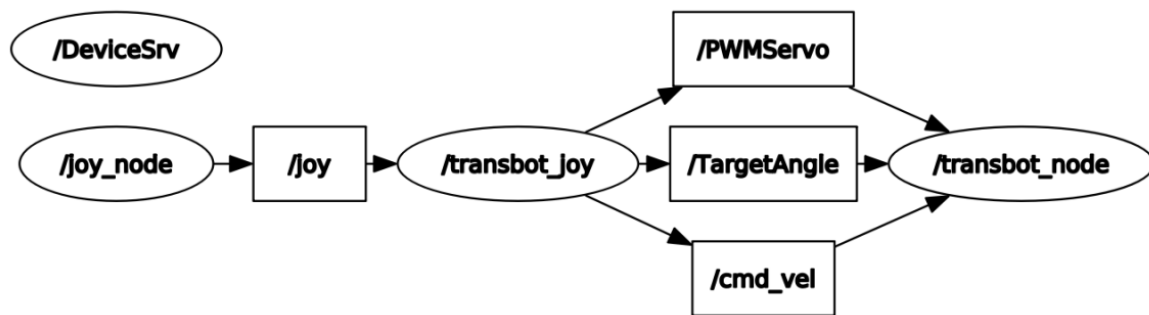
Start up command

```
roslaunch transbot_bringup joy_bringup.launch
```

View node graph

```
rqt_graph
```

Can only see the connections between topics



View service list

```
rosservice list
```

The system will print the following:

```

/Buzzer
/CamDevice
/CurrentAngle
/DeviceSrv/get_loggers
/DeviceSrv/set_logger_level
/Headlight
/RGBLight
/SetServo
/clear
/joy_node/get_loggers
/joy_node/set_logger_level
/kill
/reset
... ..

```

## 5.4、 Source code analysis

- launch file

Code path: ~/transbot\_ws/src/transbot\_bringup/launch/joy\_bringup.launch

```

<launch>
  <!--Start the camera device service-->
  <node pkg="transbot_bringup" type="DeviceSrv.py" name="DeviceSrv"
output="screen"/>
  <!--Start Transbot bottom node-->
  <node pkg="transbot_bringup" type="transbot_driver.py" name="transbot_node"
required="true" output="screen">
    <param name="imu" value="/transbot/imu"/>
    <param name="vel" value="/transbot/get_vel"/>
    <param name="kp" value="1.0"/>
    <param name="ki" value="0.0"/>
    <param name="kd" value="4.0"/>
  </node>
  <!--Start handle control node-->
  <include file="$(find transbot_ctrl)/launch/transbot_joy.launch"/>
</launch>

```

Node 【DeviceSrv】 starts the camera device service: obtains the current camera device number, and publishes whether it is currently connected to the Astra camera.

- py file

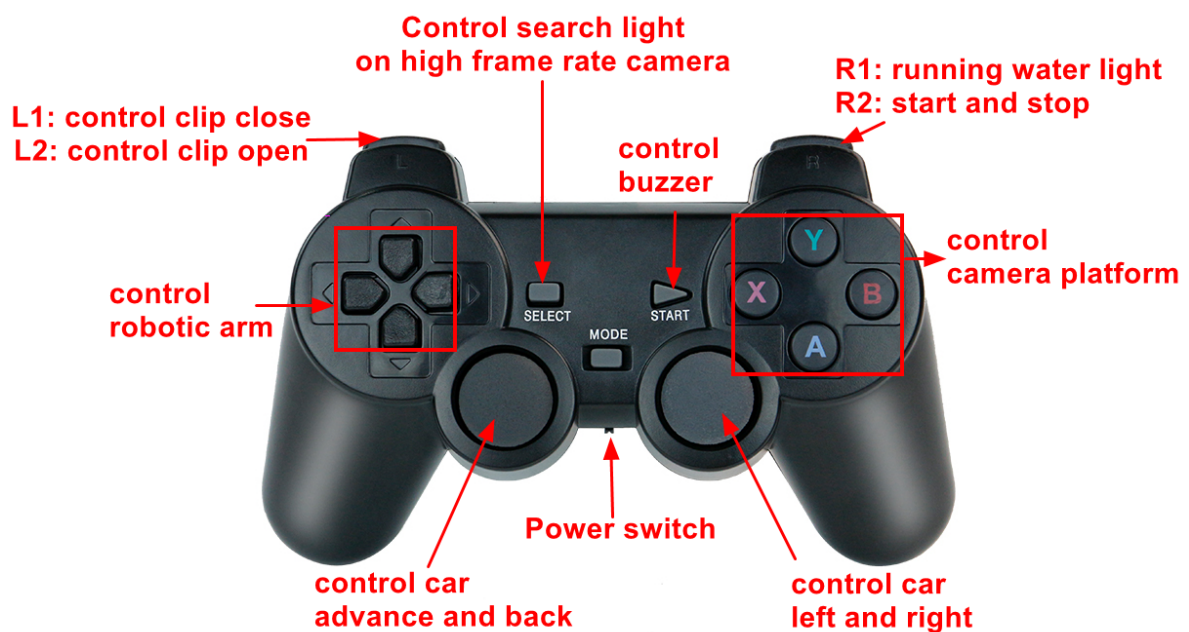
Code path: ~/transbot\_ws/src/transbot\_ctrl/scripts/transbot\_joy.py

```
arm_thread = threading.Thread(target=self.analyse_PWM())
arm_thread.setDaemon(True)
arm_thread.start()
```

Start the thread, get the currently connected camera device in the 【self.analyse\_PWM()】 function, which is convenient for processing different cameras, and turn on the loop to control the gimbal servo and robotic arm.

```
def buttonCallback(self, joy_data):
    '''
    Obtain the wireless controller receiving signal
    [1: Clamp, 2: Release, upper left: joint2+, lower left: joint2-, left
    left: joint1 upper, left and right joint1: lower]
    '''
    if not isinstance(joy_data, Joy): return
    # rospy.loginfo("joy_data.buttons:", joy_data.buttons)
    # rospy.loginfo("joy_data.axes:", joy_data.axes)
    if self.user_name == "pi": self.user_pi(joy_data)
    else: self.user_jetson(joy_data)
    # rospy.loginfo("linear_Gear: {},angular_Gear:
    {}".format(self.linear_Gear,self.angular_Gear))
    #rospy.loginfo("linear_speed: {},angular_speed:
    {}".format(linear_speed,angular_speed))
```

## 5.5、Handle control effect





# Appendix

## jetson nano

```
joy_data.buttons:
header:
  seq: 335
  stamp:
    secs: 1628324636
    nsecs: 962988952
  frame_id: "/dev/input/js0"
axes: [0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0, 0.0]
buttons: [0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0]
```

axes (8)

Code analysis	Handle button	Car control
axes[0]	Left rocker	
axes[1]	Left rocker	advance and back
axes[2]	Right rocker	left and right
axes[3]	Right rocker	
axes[4]		
axes[5]		
axes[6]	Left button	Arm-1
axes[7]	Left button	Arm-2

buttons (15)

Code analysis	Handle button	Car control
buttons[0]	A	camera platform move down
buttons[1]	B	camera platform move right
buttons[2]		
buttons[3]	X	camera platform move left
buttons[4]	Y	camera platform move up
buttons[5]		
buttons[6]	L1	Arm-clip close
buttons[7]	R1	running water light
buttons[8]	L2	Arm-clip open
buttons[9]	R2	control switch
buttons[10]	SELECT	search light on high frame rate camera
buttons[11]	START	buzzer
buttons[12]		
buttons[13]	Press left rocker	Linear speed [ 0.15 , 0.3 , 0.45 ]
buttons[14]	Press right rocker	Angular speed [ 0.5 , 1 , 1.5 , 2 ]

## Raspberry Pi

```

joy_data.buttons: header:
  seq: 264
  stamp:
    secs: 1628326479
    nsecs: 848359307
  frame_id: "/dev/input/js0"
axes: [-0.0, -0.0, 0.0, -0.0, -0.0, 0.0, 0.0, 0.0]
buttons: [0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0, 0]

```

axes (8)

Code analysis	Handle button	Car control
axes[0]	Left rocker	
axes[1]	Left rocker	advance and back
axes[2]	L2(press:-1 , release:1)	Arm clip
axes[3]	Right rocker	left and right
axes[4]	Right rocker	
axes[5]	R2(press:-1 , release:1)	control switch
axes[6]	Left button	Arm-1
axes[7]	Left button	Arm-2

buttons (11)

Code analysis	Handle button	Car control
buttons[0]	A	camera platform move down
buttons[1]	B	camera platform move right
buttons[2]	X	camera platform move left
buttons[3]	Y	camera platform move up
buttons[4]	L1	Arm clip
buttons[5]	R1	running water light
buttons[6]	SELECT	search light on high frame rate camera
buttons[7]	START	buzzer
buttons[8]	MODE	
buttons[9]	Press left rocker	Linear speed [ 0.15 , 0.3 , 0.45 ]
buttons[10]	Press right rocker	Angular speed [ 0.5 , 1 , 1.5 , 2 ]