

CSCI 545 Lab 1 - Report

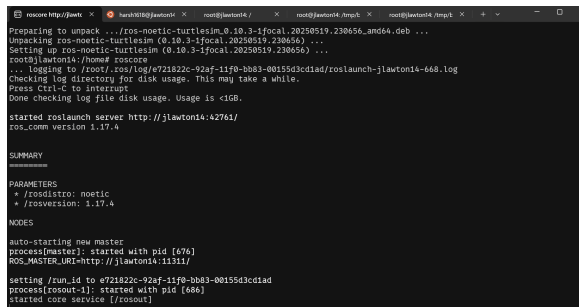
Jailbreakers

ROS Exercises

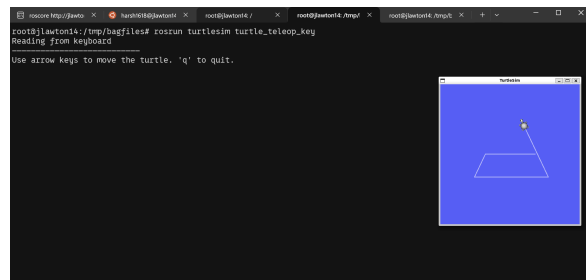
Question 6 - Turtlesim Data Flow

The `/teleop_turtle` node publishes velocity commands on the `/turtle1/cmd_vel` topic, which the `/turtlesim_node` subscribes to. This shows the flow of data: key inputs are converted to velocity messages by the teleop node and sent to the turtlesim node, which moves the turtle accordingly.

Question 6 - Screenshots



(a) Running the ROS Master with `roscore`.



(b) Running the keyboard teleoperation node.



(c) The RQT graph visualizing the connection between the `/teleop_turtle` publisher and the `/turtlesim` subscriber over the `/turtle1/cmd_vel` topic.

Question 6 - Core ROS Commands

The following are fundamental command-line tools for interacting with the ROS system:

`rosservice` is used to call services, which are request/response style operations in ROS.

`rostopic` allows you to view, publish, and subscribe to topics, which are continuous data streams.

`rosparam` manages parameters on the parameter server, such as configuration values.

`rosvbag` is used to record and replay topic data, which is useful for debugging or testing without live inputs.

Question 7 - Publishers and Subscribers

This exercise demonstrates the fundamental **publish/subscribe model** in ROS by creating two communicating nodes. First, a publisher node is written in Python to broadcast messages of a specific type onto a named channel called a topic (e.g., `'chatter'`). Concurrently, a subscriber node is created to listen to that same topic. The subscriber uses a callback function that automatically executes to process each message it receives, typically by printing it to the console. To run the system, `rosvcore` is started first, followed by launching the publisher and subscriber nodes in separate terminals using `rosvrun`. Successful communication is verified by observing the subscriber's output and using command-line tools like `rostopic list` and `rostopic echo` to inspect the topic's activity.

```
INFO [1758064071.504552]: /listener_2461_1758064064227I heard hello world 1758064071.501925
INFO [1758064071.605052]: /listener_2461_1758064064227I heard hello world 1758064071.601925
INFO [1758064071.704668]: /listener_2461_1758064064227I heard hello world 1758064071.701742
INFO [1758064071.805297]: /listener_2461_1758064064227I heard hello world 1758064071.801774
INFO [1758064071.904557]: /listener_2461_1758064064227I heard hello world 1758064071.901815
INFO [1758064072.004853]: /listener_2461_1758064064227I heard hello world 1758064072.001740
INFO [1758064072.105154]: /listener_2461_1758064064227I heard hello world 1758064072.101819
INFO [1758064072.204619]: /listener_2461_1758064064227I heard hello world 1758064072.201742
INFO [1758064072.304877]: /listener_2461_1758064064227I heard hello world 1758064072.301715
INFO [1758064072.405064]: /listener_2461_1758064064227I heard hello world 1758064072.401686
INFO [1758064072.504886]: /listener_2461_1758064064227I heard hello world 1758064072.501749
INFO [1758064072.605597]: /listener_2461_1758064064227I heard hello world 1758064072.601822
INFO [1758064072.705263]: /listener_2461_1758064064227I heard hello world 1758064072.701931
INFO [1758064072.805055]: /listener_2461_1758064064227I heard hello world 1758064072.801713
INFO [1758064072.904174]: /listener_2461_1758064064227I heard hello world 1758064072.901744
INFO [1758064073.004458]: /listener_2461_1758064064227I heard hello world 1758064073.001685
INFO [1758064073.104616]: /listener_2461_1758064064227I heard hello world 1758064073.101730
INFO [1758064073.204897]: /listener_2461_1758064064227I heard hello world 1758064073.201722
INFO [1758064073.305015]: /listener_2461_1758064064227I heard hello world 1758064073.301730
```

(a) Subscriber Logs.

```
root@jlawton14:/tmp/bagfiles# rostopic list
/chatter
/rosout
/rosout_agg
```

(b) Validating the topic.

Team Contributions

The five members of our team made equal contributions to this lab (20% each). While each member began by independently setting up their environment and working through the exercises, the final report was a collaborative effort. We collated our individual results, discussed our findings, and jointly wrote the final document.

Resources Consulted

- Official documentation of ROS for more information on packages.
- ROS tutorial for writing a pub-sub model.
- LLMs for in-depth explanations and for some formatting help with LaTeX.