

Robotics
Laboratory

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Abstract

The course is composed by a set of lectures on autonomous robotics, ranging from the main architectural patterns in mobile robots and autonomous vehicles to the description of sensing and planning algorithms for autonomous navigation. The course outline is:

- Mobile robots' kinematics.
- Sensors and perception.
- Robot localization and map building.
- Simultaneous Localization and Mapping (SLAM).
- Path planning and collision avoidance.
- Robot development via ROS.

Contents

1	Introduction	1
1.1	Middleware origins and usage	1
1.2	Middlewares	1
2	Robot Operating System	3
2.1	Introduction	3
2.2	Computational graph	4
2.2.1	Nodes	4
2.2.2	Master	4
2.2.3	Topics	5
2.2.4	Messages	5
2.2.5	Services	6
2.2.6	Parameter server	6
2.2.7	Bags	6
2.2.8	ROScore	6
2.3	ROS file system	6
2.3.1	Packages	7
2.3.2	Metapackages	7
3	ROS commands and files	9
3.1	Basic commands	9
3.1.1	Topics	9
3.1.2	Nodes	10
3.1.3	Services	10
3.2	Bags and saves	10
3.3	Publisher	11
3.4	Subscriber	12
3.5	Other files	12
3.6	Project compilation	14
A	Other useful commands	15
A.1	Tmux	15

CHAPTER 1

Introduction

1.1 Middleware origins and usage

Middleware was introduced by d'Agapeyeff in 1968, the concept of a wrapper emerged in the 1980s as a bridge between legacy systems and new applications. Today, it is prevalent across various domains, including robotics. Examples outside of robotics include Android, SOAP, and Web Services.

The concept of Middleware is widely recognized in software engineering. It serves as a computational layer, acting as a bridge between applications and low-level details. It's important to note that Middleware is more than just a collection of APIs and libraries.

Issues The challenge lies in fostering cooperation between hardware and software components. Robotics systems face architectural disparities that affect their integration. Ensuring software reusability and modularity is also a critical concern in this context.

Main features The key attributes of middlewares include:

- *Portability*: offering a unified programming model irrespective of programming language or system architecture.
- *Reliability*: middlewares undergo independent testing, enabling the development of robot controllers without the need to delve into low-level details, while leveraging robust libraries.
- *Manage the complexity*: handling low-level aspects through internal libraries and drivers within the middleware, thereby reducing programming errors and speeding up development time.

1.2 Middlewares

Several middleware have been developed in recent years:

- *OROCOS*: originating in December 2000 as an initiative of the EURON mailing list, OROCOS evolved into a European project with three partners: K.U. Leuven (Belgium),

LAAS Toulouse (France), and KTH Stockholm (Sweden). The requirements for OROCOS encompass open source licensing, modularity, flexibility, independence from specific robot industries, compatibility with various devices, software components covering kinematics, dynamics, planning, sensors, and controllers, and a lack of dependency on a singular programming language. The structure includes:

- Real-Time Toolkit (RTT): offering infrastructure and functionalities tailored for real-time robot systems and component-based applications.
 - Component Library (OCL): supplying ready-to-use components such as drivers, debugging tools, path planners, and task planners.
 - Bayesian Filtering Library (BFL): featuring an application-independent framework encompassing (Extended) Kalman Filter and Particle Filter functionalities.
 - Kinematics and Dynamics Library (KDL): facilitating real-time computations for kinematics and dynamics.
- *ORCA*: the project’s objective is to emphasize software reuse in both scientific and industrial applications. Its key properties include enabling software reuse through the definition of commonly-used interfaces, simplifying software reuse via high-level libraries, and encouraging software reuse through regularly updated software repositories. ORCA defines itself as an “unconstrained component-based system”.

The primary distinction between OROCOS and ORCA lies in their communication toolkits. OROCOS utilizes CORBA, whereas ORCA employs ICE. ICE, a contemporary framework created by ZeroC, functions as an open-source commercial communication system. ICE offers two fundamental services: the IceGrid registry (Naming service), which facilitates logical mapping between various components, and the IceStorm service (event service), which forms the foundation for publisher-subscriber architecture.

- *OpenRTM*: RT-Middleware (RTM) serves as a widely adopted platform standard for assembling robot systems by integrating software modules known as robot functional elements (RTCs). These modules include components such as camera, stereo vision, face recognition, microphone, speech recognition, conversational, head and arm, and speech synthesis. OpenRTM-AIST (Advanced Industrial Science and Technology) is built upon CORBA technology to realize the extended specifications of RTC implementation.
- *BRICS*: the objective is to uncover the most effective strategies for developing robotic systems by examining several critical areas: Initially, by thoroughly examining the weaknesses found in current robotic projects. Subsequently, by delving into the integration between hardware and software components within these systems. Thirdly, by advocating for the incorporation of model-driven engineering principles in the development process. Moreover, by creating a tailored Integrated Development Environment (IDE) specifically for robotic projects, known as BRIDE Finally, by defining benchmarks aimed at evaluating the strength and effectiveness of projects based on BRICS principles.
- *ROS*: introduced by Willow Garage in 2009, the Robot Operating System (ROS) serves as a meta-operating system tailored for robotics, boasting a diverse ecosystem replete with tools and programs. ROS has expanded to encompass a vast global community of users. The developer community stands out as one of ROS’s most significant features.

Robot Operating System

2.1 Introduction

The key features of ROS:

1. *Decentralized framework*: ROS operates on a decentralized architecture, facilitating robust communication and coordination among various components.
2. *Code reusability*: ROS promotes the reuse of code, allowing developers to efficiently leverage existing modules and algorithms for faster development.
3. *Language neutrality*: ROS supports multiple programming languages, enabling developers to work in their preferred language while seamlessly integrating with the ROS ecosystem.
4. *Seamless real robot and simulation testing*: ROS provides an environment for easy testing on both real robots and simulations, ensuring smooth transition from development to deployment.
5. *Scalability*: ROS is designed to scale efficiently, accommodating projects of various sizes and complexities without compromising performance or functionality.

ROS is composed by the following elements:

- *File system utilities*: ROS provides tools for managing files and directories, simplifying data organization and access within the ROS environment.
- *Construction tools*: ROS offers construction tools to streamline the development process, facilitating the creation and configuration of robotic systems and components.
- *Package management*: ROS includes robust package management capabilities, allowing users to easily install, update, and manage software packages and dependencies.
- *Monitoring and graphical user interfaces (GUIs)*: ROS features monitoring tools and graphical user interfaces to visualize and analyze system behavior, aiding in debugging, optimization, and user interaction.
- *Data logging*: ROS supports data logging mechanisms for recording and analyzing sensor data, system state, and other relevant information, facilitating research, analysis, and debugging tasks.

2.2 Computational graph

The computation graph is the peer-to-peer network of ROS processes that are processing data together.

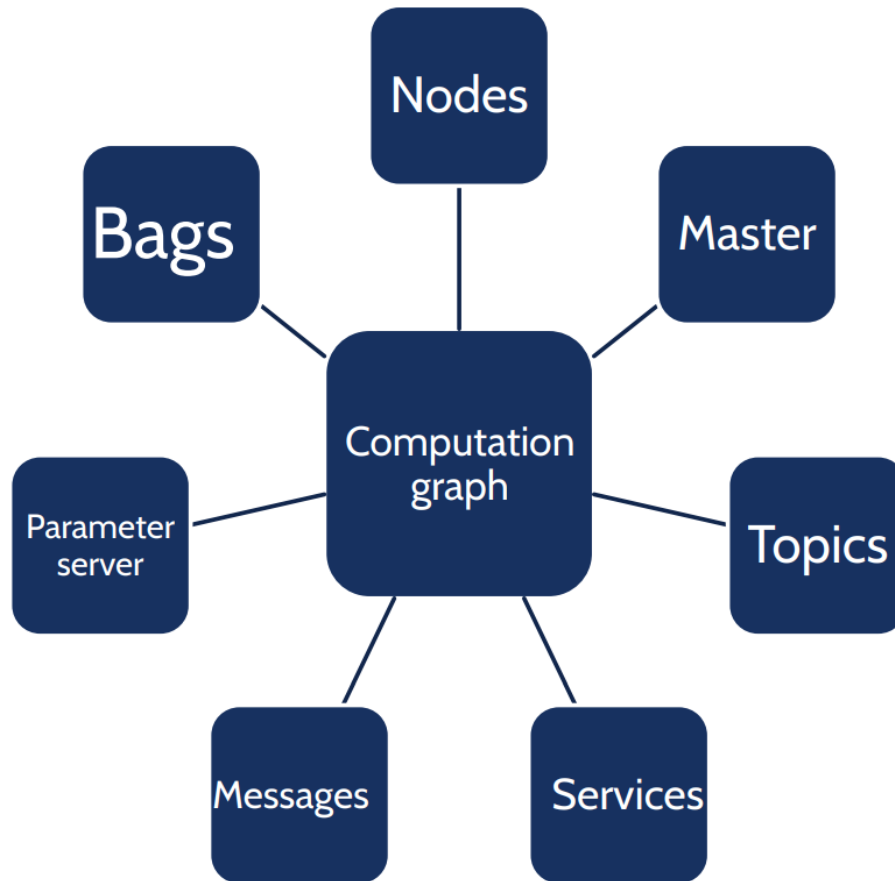


Figure 2.1: ROS computational graph

2.2.1 Nodes

ROS executable units include Python scripts and C++ compiled source code. They are processes responsible for computation within the ROS framework. These units, referred to as nodes, exchange information through a graph structure. Nodes are designed to operate at a fine-grained scale and are integral components of robot systems, which are composed of multiple interconnected nodes. To initiate a node, the following command is utilized:

```
roslaunch package_name node_name
```

2.2.2 Master

The ROS Master serves as the central hub, facilitating naming and registration services crucial for node interactions. In every system, including distributed architectures, there exists a single master. This centralized entity enables ROS nodes to effectively locate each other.

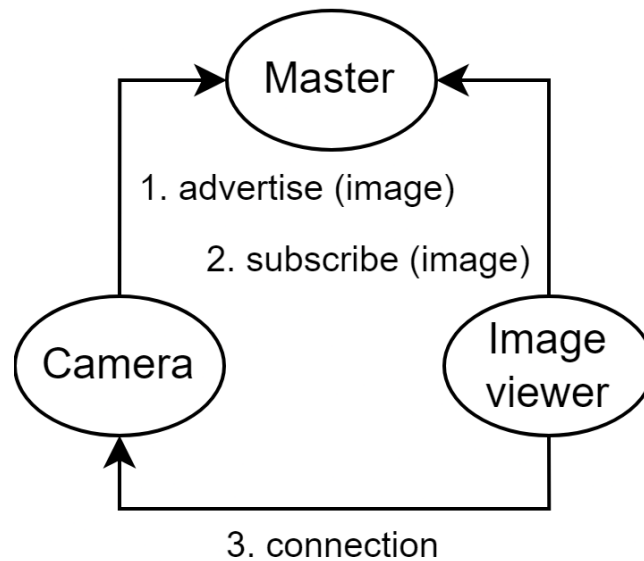


Figure 2.2: ROS master

In this scenario, the camera node advertises the master with an image, making it available on a specific topic. Subsequently, the image viewer node subscribes to the same topic through the master. Once the requested topic is found, the ROS master facilitates communication by providing the node name, allowing the subscriber to establish communication with the node that generated the image. This interaction demonstrates the pivotal role of the ROS master in mediating communication between nodes in the ROS ecosystem.

2.2.3 Topics

Topics serve as named channels for communication within the ROS framework, implementing the publish/subscribe paradigm. They facilitate communication between nodes by allowing multiple nodes to publish messages on a topic and multiple nodes to read those messages from the same topic. Topics are associated with specific message types, but they do not guarantee message delivery.

It's advisable to avoid scenarios where multiple talkers are connected to the same topic in ROS. This is because ROS lacks a mechanism to discern the origin of a message in such cases.

2.2.4 Messages

Communication on topics involves the exchange of messages, which define the type of information being transmitted. A wide range of predefined message types is available. Additionally, it is possible to create custom messages using a straightforward language. These custom messages can incorporate existing message types along with base types as needed. The available message types include:

```
std_msgs/Header.msgs
// uint32 seq
// time stamp
// string frame_id

std_msgs/String.msg
```



```
// string data

sensor_msgs/Joy.msg
// std_msgs/Header header
// float32[] axes
// int32[] buttons
```

2.2.5 Services

Services function akin to remote function calls within ROS, adhering to the client/server paradigm. When a service call is made, the code waits for its completion, ensuring a guarantee of execution. Services utilize message structures for their operation.

2.2.6 Parameter server

The parameter server is a shared, network-accessible multivariable dictionary utilized by nodes for storing and accessing parameters during runtime. It's not optimized for performance or data exchange. This server is linked to the master, constituting one of the functionalities provided by ROScore. The procedure for accessing and modifying data in the parameter server is accomplished using the following command:

```
rosparam [set|get] name value
```

The parameter server can store a range of data types, including 32-bit integer, Boolean, string, double, ISO8601 date, and base64-encoded binary data.

2.2.7 Bags

Bags serve as a file format (*.bag) designed for storing and replaying messages within ROS. They constitute the primary mechanism for data logging, capable of recording all exchanges occurring on the ROS graph, including messages, services, parameters, and actions. Bags are essential tools for data analysis, storage, visualization, and algorithm testing within the ROS ecosystem. The commands used to modify the bag is:

```
rosvim record -a
```

2.2.8 ROScore

ROScore is a foundational component of ROS-based systems, comprising nodes and programs essential for operation. It must be active to facilitate communication among ROS nodes. Launching ROScore via the command initiates its elements, which include a ROS master, a ROS parameter server, and a ROSout logging node.

2.3 ROS file system

The foundation of the ROS file system revolves around packages, depicted in the diagram below.

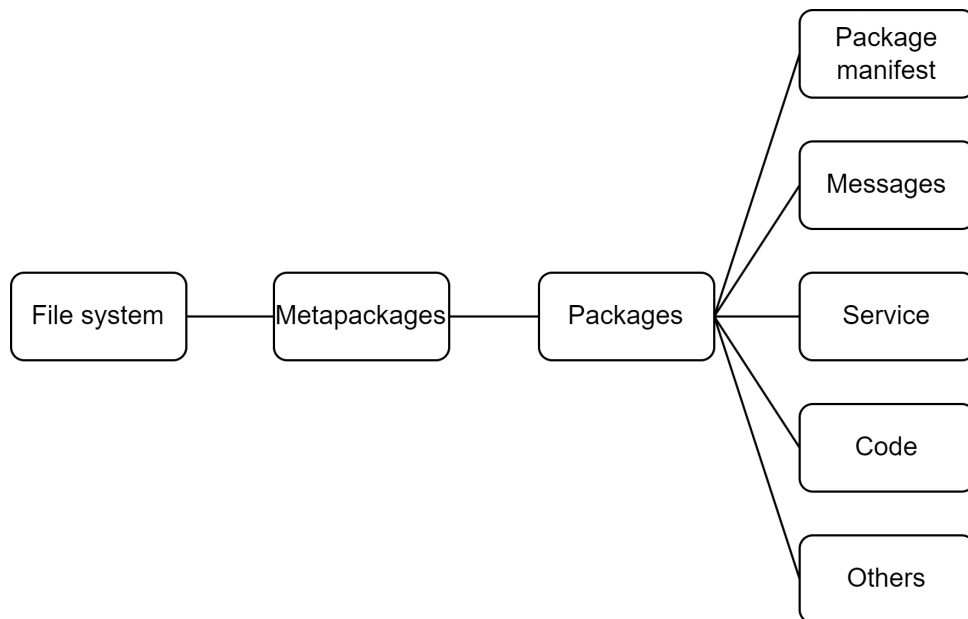


Figure 2.3: ROS file system

Packages serve as the fundamental units within the ROS file system. They are essential references for most ROS commands and encompass nodes, messages, and services. Each package is described by a `package.xml` file and acts as a mandatory container for its contents.

Additionally, there are metapackages, which aggregate logically related elements. Unlike packages, metapackages are not directly utilized when navigating the ROS file system. They contain other packages and are described by a `package.xml` file as well, but they are not obligatory components.

2.3.1 Packages

Packages serve as fundamental units within the ROS file system, acting as the cornerstone for most ROS commands. They encapsulate nodes, messages, and services, providing a structured organization for ROS functionalities. Each package is described by a `package.xml` file, serving as a mandatory container that delineates the package's properties and dependencies. The general structure of a package includes the following components:

- Folder Structure:
 - `/src`, `/include`, `/scripts` (for coding).
 - `/launch` (for launch files).
 - `/config` (for configuration files).
- Required Files:
 - `CMakeLists.txt`: contains build rules for catkin.
 - `package.xml`: provides metadata for ROS.

2.3.2 Metapackages

Metapackages are collections of logically related elements within ROS, serving as aggregations rather than individual components. Unlike regular packages, they are not typically used when

navigating the ROS file system. Metapackages encompass other packages and are described by a `package.xml` file, yet they are not obligatory structures within ROS.

CHAPTER 3

ROS commands and files

3.1 Basic commands

To initiate ROScore within a tmux terminal, execute the following command:

```
roscore
```

3.1.1 Topics

To view active topics, use the command:

```
rostopic list
```

To publish a new permanent topic, utilize:

```
rostopic pub /topic_name message_type message_name data
```

For publishing a new temporary topic, use:

```
rostopic pub --once /topic_name message_type message_name data
```

To publish a new topic at a specific frequency, employ:

```
rostopic pub -r frequency /topic_name message_type message_name data
```

To check the running frequency of a particular topic, execute:

```
rostopic hz /topic_name
```

To display the content of a specific topic, input:

```
rostopic echo /topic_name
```

To view information about a topic with a graphical user interface (GUI), employ:

```
rqt_topic
```

3.1.2 Nodes

To view active nodes, utilize the command:

```
roscall list
```

To access information about a specific node, use:

```
roscall info /name
```

For viewing information about a specific node with a graphical user interface (GUI), use:

```
rqt_graph
```

To initiate a node, the command is:

```
roscall package_name node_name
```

For redirecting the topic associated with a particular node, utilize:

```
roscall package_name node_name /old_topic:=/new_topic
```

To generate a node resembling an existing one but with an altered name, execute:

```
roscall \package_name \node_name --name:=\new_node_name
```

3.1.3 Services

To invoke a service, employ:

```
rosservice call /service_name parameters
```

3.2 Bags and saves

To record a series of commands given to a specific topic we write:

```
roscall record /topic_name
```

To check the data inside a bag we write

```
roscall info bag_name.bag
```

To play the data inside a bag we write

```
roscall play bag_name.bag
```

To play in loop the data inside a bag we write

```
roscall play -l bag_name.bag
```

To visualize data from a playing a bag we write:

```
rviz
```

Alternatively, to visualize simple numeric data we write:

```
roscall plotjuggler plotjuggler
```

And select ROS topic subscriber as the source streaming. From the time series list we can finally select the specific topic.

3.3 Publisher

The structure of a publisher is as follows:

```
#include "ros/ros.h"
#include "std_msgs/String.h"

int main(int argc, char **argv) {

    // initialize the node with the name "talker"
    // ros::init_options::AnonymousName initialize the node without a name
    ros::init(argc, argv, "talker");

    // handle used to call all the ros related functions
    ros::NodeHandle n;

    // create the publisher called "chatter_pub" with the type of message
    // the message is a simple "String" and it is publish on the topic "chatter"
    ros::Publisher chatter_pub = n.advertise<std_msgs::String>("chatter", 1);

    // we want a loop with a running frequency of ten
    ros::Rate loop_rate(10);

    int count = 0;

    // automatic check on the condition
    while (ros::ok()) {

        // message "msg" creation
        std_msgs::String msg;

        // setting the field in the message, "String" has only this field
        msg.data = "hello world!";

        // print on the log console of the message
        ROS_INFO("%s", msg.data.c_str());

        // message publishing
        chatter_pub.publish(msg);

        // used for the loop to let the system know that one loop is done
        ros::spinOnce();

        // sleep for the requested time
        loop_rate.sleep();
        ++count;
    }
    return 0;
}
```

3.4 Subscriber

The structure of a subscriber is as follows:

```
#include "ros/ros.h"
#include "std_msgs/String.h"

// code executed when we received a message
void chatterCallback(const std_msgs::String::ConstPtr& msg) {
    ROS_INFO("I heard: [%s]", msg->data.c_str());
}

int main(int argc, char **argv) {

    // initialize the node with the name "listener"
    ros::init(argc, argv, "listener");

    // handle used to call all the ros related functions
    ros::NodeHandle n;

    // create the subscriber called "sub" with the topic "chatter"
    // the function "chatterCallback" is called when something is published
    ros::Subscriber sub = n.subscribe("chatter", 1, chatterCallback);

    // standard used outside a loop when the code is executed
    ros::spin();

    return 0;
}
```

3.5 Other files

The CMakeLists file has the following structure:

```
cmake_minimum_required(VERSION 2.8.3)
// name of the package
project(pub_sub)

## Find catkin and any catkin packages
find_package(catkin REQUIRED COMPONENTS roscpp std_msgs)

## Declare a catkin package
catkin_package()

## Build talker and listener
include_directories(include ${catkin_INCLUDE_DIRS})

// publisher executables
```

```
add_executable(pub src/pub.cpp)
target_link_libraries(pub ${catkin_LIBRARIES})

// subscriber executables
add_executable(sub src/sub.cpp)
target_link_libraries(sub ${catkin_LIBRARIES})
```

The package.xml file has the following structure:

```
<?xml version="1.0"?>
<package format="2">
  <!-- package name -->
  <name>pub_sub</name>
  <version>0.0.0</version>
  <description>The pub_sub package</description>

  <!-- One maintainer tag required, multiple allowed, one person per tag -->
  <!-- Example: -->
  <!-- <maintainer email="jane.doe@example.com">Jane Doe</maintainer> -->
  <maintainer email="simone@todo.todo">simone</maintainer>

  <!-- One license tag required, multiple allowed, one license per tag -->
  <!-- Commonly used license strings: -->
  <!--   BSD, MIT, Boost Software License, GPLv2, GPLv3, LGPLv2.1, LGPLv3 -->
  <license>TODO</license>

  <!-- Url tags are optional, but multiple are allowed, one per tag -->
  <!-- Optional attribute type can be: website, bugtracker, or repository -->
  <!-- Example: -->
  <!-- <url type="website">http://wiki.ros.org/pub_sub</url> -->

  <!-- Author tags are optional, multiple are allowed, one per tag -->
  <!-- Authors do not have to be maintainers, but could be -->
  <!-- Example: -->
  <!-- <author email="jane.doe@example.com">Jane Doe</author> -->

  <!-- The *depend tags are used to specify dependencies -->
  <!-- Dependencies can be catkin packages or system dependencies -->
  <!-- Examples: -->
  <!-- Shortcut for packages that are both build and exec dependencies -->
  <!--   <depend>roscpp</depend> -->
  <!--   Note that this is equivalent to the following: -->
  <!--   <build_depend>roscpp</build_depend> -->
  <!--   <exec_depend>roscpp</exec_depend> -->
  <!-- Use build_depend for packages you need at compile time: -->
  <!--   <build_depend>message_generation</build_depend> -->
  <!-- Use build_export_depend for packages to build against this package: -->
  <!--   <build_export_depend>message_generation</build_export_depend> -->
```



```
<!-- Use buildtool_depend for build tool packages: -->
<!--   <buildtool_depend>catkin</buildtool_depend> -->
<!-- Use exec_depend for packages you need at runtime: -->
<!--   <exec_depend>message_runtime</exec_depend> -->
<!-- Use test_depend for packages you need only for testing: -->
<!--   <test_depend>gtest</test_depend> -->
<!-- Use doc_depend for packages needed for building documentation: -->
<!--   <doc_depend>doxygen</doc_depend> -->
<buildtool_depend>catkin</buildtool_depend>
<build_depend>roscpp</build_depend>
<build_export_depend>roscpp</build_export_depend>
<build_export_depend>std_msgs</build_export_depend>
<exec_depend>roscpp</exec_depend>
<exec_depend>std_msgs</exec_depend>

<!-- The export tag contains other, unspecified, tags -->
<export>
  <!-- Other tools can request additional information be placed here -->

</export>
</package>
```

3.6 Project compilation

To compile the file, ensure you're located within the directory `catkin_ws` and execute `catkin_make`. Upon successful completion, verify the presence of a folder named `build`. Afterwards, initiate the nodes with the following command:

```
roslaunch \package_name \node_name
```

APPENDIX A

Other useful commands

A.1 Tmux

To create a new terminal session, use:

```
tmux new -s session1
```

To exit the current terminal session, either:

```
tmux detach
```

or press: `ctrl + b + d`.

To join an existing session, execute:

```
tmux a
```

To split the terminal into multiple sections:

- Horizontal split: `ctrl + b + "`.
- Vertical split: `ctrl + b + %`

To exit a split section, input:

```
exit
```

To navigate between terminals, press `ctrl + b` followed by the arrow keys.

To check active tmux sessions, use:

```
tmux ls
```

To join a specific session, utilize:

```
tmux a -t session1
```

For scrolling the page, press: `ctrl + b + [`.