COMPUTER SCIENCE ENGINEER

FINAL REPORT

Immersive Virtual Reality System

SIGVerse interaction trough Robot Operating System

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Gratitude

I wish to thank the National Institute of Informatics who gave me the opportunity to do my six-month internship in one of its laboratory. With this internship, I finalize my master's degree in computer science engineering.

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I thank the National Institute of Informatics administration staff who helped me get over all administrative steps and my interrogations. Also a thank you to Polytech'Nice Sophia who make this internship possible.

Finally I would like to say many thanks to all the people who made my study and internship possible, and encourage me during my all study - friends, familly and the all people I met who gave me good moment.

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1 Introduction

1.1 Context

1.1.1 National Institute of Informatics

The NII[1] of Tokyo is an inter university research institute which aim to develop the research in multiple domains. The Institute is focused on fields including networking software and content. The NII is composed by several laboratories which work on different international research project. One of them is directed by the associate professor Inamura Tetsunari where I am doing my internship. The Inamura laboratory works on several project, which one is SIGVerse, a simulator.

1.1.2 SIGVerse

SIGVerse is a virtual world which can model objects and agents.
This simulator has been created to give a tool for studying interactions between agents but also comprehension and knowledge in many fields.
Understanding the mechanism of intelligence of human being is the key to develop intelligent robot system. That's why this simulator is very useful.
The movement of the user can be reproduced in the virtual world thanks to the kinect and the representation of the world can be projected on the oculus. So, the user can be "inside" the simulator and interact more easily with its.
We can see in figure 1.1, the representation of an agent. This agent could be a robot too, and it is possible to program its movements or send to it a message to execute an action. That's why this simulator is well adapted to host the training and virtual competition of Robocup.
However, the use of the simulator is exclusively for SIGVerse users which limits its growth.

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[1]National Institute of Informatics

Figure 1.1: Simple agent in the virtual world

1.2 Topic

SIGVerse is limited to SIGVerse users. This topic has the goal to growth the SIGVerse community by joining the ROS[2] community.

This gathering has been chosen because of several reasons.

First of all ROS is open source like SIGVerse and has a big community who works on robots. Then ROS can provide a collection of tools, libraries, and conventions that aim to simplify the task of creating complex and robust robot behavior across a wide variety of robotic platforms.

ROS make possible to manage a robot as SIGVerse do but there is advantages to using ROS. Indeed, ROS is designed to be as distributed and modular as possible so, it encourages the collaboration to develop robot software whereas SIGVerse is not.

In this report, I am going to detail the suggested work, general idea and how ROS works. After that, I am going to detail what I started doing, architecture, topics, services, troubles...

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[2]Robot Operating System

2 Suggested work

2.1 Robot Operating System

The ROS[1] is an open source flexible framework for writing robot software. It is a collection of tools, libraries, and conventions that aim to simplify the task of creating complex and robust robot behavior across a wide variety of robotic platforms.

At the lowest level, ROS is commonly referred to as a middleware. It provides some facilities like publishing/subscribing anonymous message passing and request/response remote procedure calls. We can see in the figure 2.1 the base concept of ROS. Each entity is a node who can publish or subscribe to a topic. If a node publish to a topic, every node who subscribed to it will receive the message. Many nodes can publish in the same topic and many nodes can subscribe to the same topic. Every node can publish and/or subscribe to several nodes.

We can also see a service between two nodes, the first node can send a request with zero or more parameters to the other node who will act and respond with parameters.
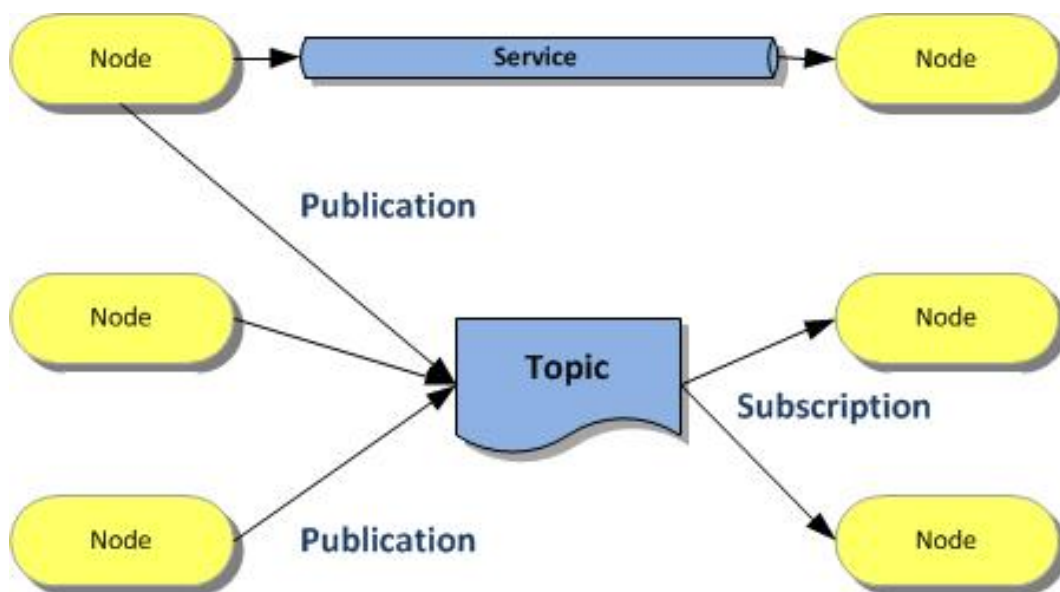

Figure 2.1: Publish/Subscribe system

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[1]Robot Operating System

2.2   SIGVerse architecture

Currently, the architecture of SIGVerse is as shown figure 2.2.
On the Linux part, the server is running with the xml file where the agent is defined and the Controller.cpp where the initialisation and actions are defined.
On the Windows part, two things, SIGViewer which is a GUI and aim to show to the user the agent on the simulator. The services are all devices which can provide data to the server. That means the kinect, the oculus,...
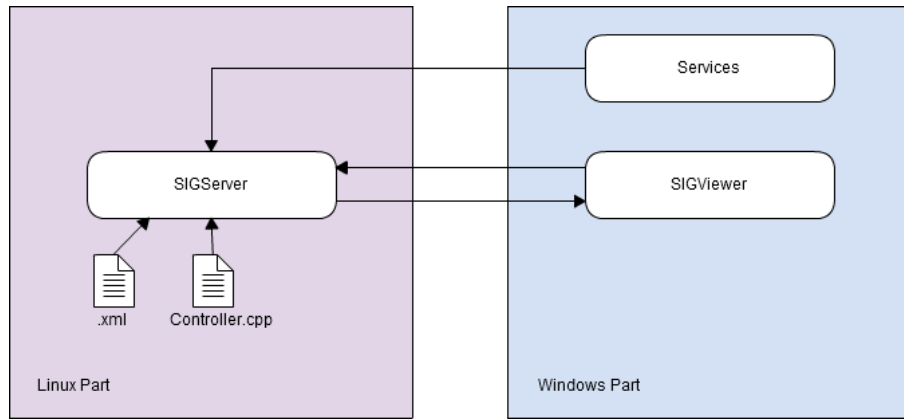

Figure 2.2: SIGVerse

2.3   Objective

As seen section 2.1, using ROS to create and manipulate agents on SIGVerse will be very useful. So, I have to design and develop an interface between SIGVerse and ROS.
This interface has to make available the features of SIGVerse from ROS, that means initializing one or more agents, make them act and make the services working though ROS.
The agents can be: robot, human or object.
The expected architecture is shown figure 2.3. We can see the SIGServer and the "Controller" inside the ROS interface, that means the user will not need to interact with SIGVerse, he only defined the agent in the xml file and then, interacting with ROS, send messages to the server though the interface. The user will not need to write the "Controller", it will be automatically generated.
This is an example with one xml file and one controller, but it will be necessary to generalise it to more than one.
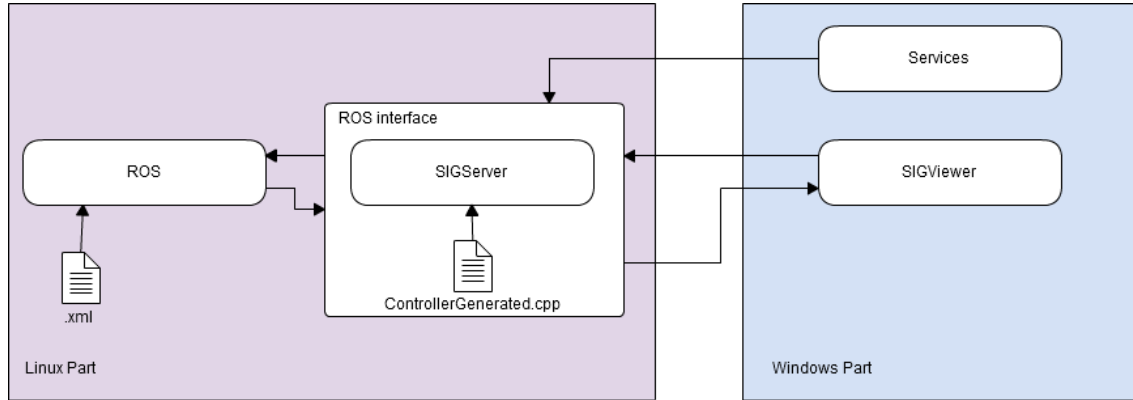
Figure 2.3: SIGVerse with ROS interface

2.4 Functionalities requiered

2.4.1 General requirement

Currently, SIGVerse has two parts: SIGServer and SIGViewer and they communicate directly together as seen figure 2.2.

The aim is to find a way for the ROS users for using SIGVerse. That means the ROS user will only write ROS code and this will be enough for manipulate the simulator.

Right now, if the ROS user wants to do it, he has to make the interface himself, mapping the SIGVerse function which is needed. That is why, a common interface with the main functions are useful. After that, the user will have the possibility to enhance it.

Three agents are available on SIGVerse: the robot, the human and the object and different actions are available for each one. But some same actions are available for many of them. Indeed the robot agent inherits from the object agent and the human can be a special robot.

2.4.2 Use case

The main use case is for the Robocup competition. Indeed, with this interface, ROS users could participate to the competition.

RoboCup is an annual international robotics competition founded in 1997.

There are many stages of competition, RoboCupRescue, RoboCup@Home, RoboCupJunior,...

The best known is the football competition where two team of robots are playing football, but the Inamura lab works on RoboCup@Home using SIGVerse. Three kinds of task are competing, the clean up task, the follow me and the EGPSR task.

In a simple clean up task, the robot detects the trash, go to take it and puts it in the trashbox detected. Points are given for every good things done like "take the trash" and "put it in the trashbox", but points are removed if a collision occurs.

The aim of the follow me task is to follow someone without collision, don't lose him and knowing in which direction after entering the elevator. Indeed, if the man entry the elevator, the robot will enter too but the man will not be able to go out before the robot do it.

The EGPSR task is the interaction between the human and the robot. The man asks the robot for an object in a room and the robot has to go to the right room and get it back.

First of all, the clean up task has to work with ROS, that means the methods used with the robot and some methods of objects.

After that, there is a third agent, the human, so the follow up task will be a pertinent example.

2.4.3   To go further

To go further, the adaptation of some ROS functionalities to SIGVerse will be a great advantage for SIGVerse. Indeed, some actions can take a lot of time to program inside SIGVerse whereas just few information can be needed by a ROS package to obtain the same information.

Two packages ROS are suggested, SLAM[2] and ik[3].

SLAM

The SLAM problem appears like the chicken and egg problem. Indeed, it is the fact of creating the map at the same time as localizing himself inside the map.

The main reason of this package choose is because inside SIGVerse, the robot know the map because it is inside a simulator and has access to it. I think to be closer the reality, the robot has to discover the map and no taking it and making his path planning.

As explained on the ros tutorial of the slam_gmapping package, this package can be used like a black box. We only need to know what the package need as entry and what it will produce.

Inverse Kinematics

Inverse kinematics is the use of the kinematics equations in order to provide the desired position of the end effector. That means, with the defined position of the end effector, the inverse kinematics found the position of all joints of the arm.

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[2]Simultaneous Localization And Mapping
[3]Inverse Kinematics

This choice is due to the observation of this lack of this functionnality very important inside SIGVerse. Indeed, to program the user side of the Robocup demonstration, grasping an object with an arm was not instinctive at all. The user has to find each angle (shoulder, elbow,...) by himself and animate the arm.

2.5   ROS and SIGVerse

On SIGVerse an agent is defined by an XML file for his representation and a "controller" for his dynamic. The dynamic allows an agent to act, receive message or send message.
Currently, the user has to transform the "Controller" into a ROS node himself, defining the interface for each method needed.
We can see in figure 2.4 an example. Indeed, we can see the "Controller" inside the server who is also a ROS node. That is why it can publish a message to a topic and subscribe to "Velocity Topic". After that, any ROS node can be created and publish or subscribe to topics, the SIGVerse agent can receive instructions from a topic or a service.

In this example figure 2.4 given on the SIGVerse wiki page[3], the "Controller" launch the ROS node when the simulation starts and the topics are created. However, we want the user to write only ROS code and do not bother himself with the "Controller" and SIGVerse functioning.
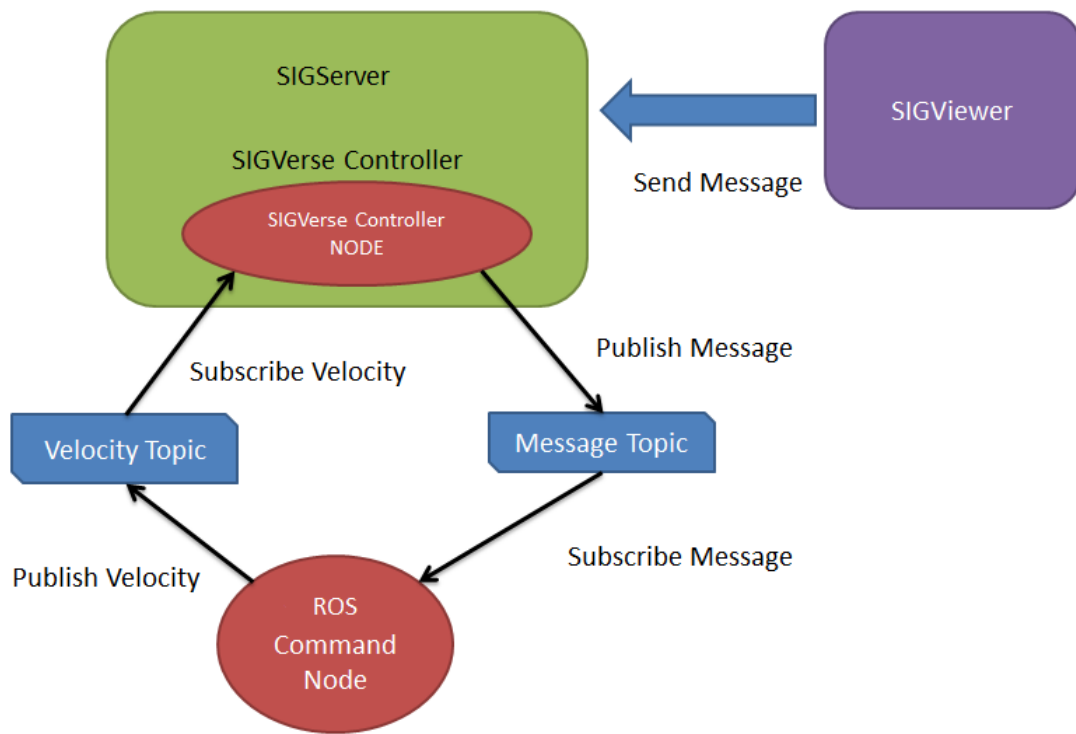
Figure 2.4: SIGVerse controller sending and receiving message

3 Work performed

3.1 Controller

Each "Controller" associated to an agent on the world inherit from the main class "Controller" of SIGVerse. That is why each of them has the same dynamic shown figure 3.1.

When the simulation starts on the SIGViewer, each "Controller" is initialized running "onInit" method. After that the "onAction" method is running regularly, it can be every 1 seconds like 0.1, 0.5,... It is defined by the return value of "onAction" method.
If a collision occurs between the agent and something else, "onCollision" is executed.
If the agent receives a message, "onRecvMsg" is executed.

In any case, "onAction" is running until the simulation stops. If the simulation restarts, "onInit" is not executed, the simulation continues where it stopped.
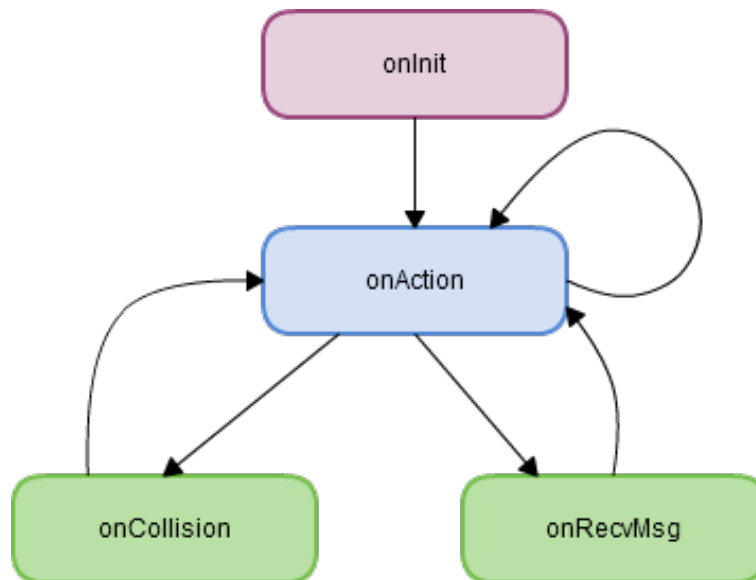

Figure 3.1: Dynamic of the "Controller"

3.2 Architecture

3.2.1 General objective

On the SIGServer, severals "Controller" can run at the same time, because there are one for each agent in the simulator and their types can be different. For exemple, we can have a "Controller" for a Robot and "Controller" for an object. The principal difference between them is that a Robot controller do not apply the same method to the agent than an object, indeed the robot can move, not an object. But they have the same dynamic, section 3.1.
If we have three robots in the simulator, that means three "Controller".

We can see figure 3.2 how the interface has to work. Several nodes can send information to topics which can be the same or not. This is the ROS part. And these topics are subscribed by the "Controller" of SIGServer.
As we can see, the same node can publish to the same node "Topic 4" or one node can publish to several nodes "Node 1".
However, different "Controller" cannot publish or subscribe to the same topic. The reason is that the ROS user do not have to write the "Controller" or edit it neither, it will be generated and I can not know if the user want the same behaviour between two or more agents. If the user wants this behaviour, he will have to send the same message to severals topics.

As we can see figure 3.2 a service can be called too. The difference with publishing/subscribing is that a request is sent and the "Controller" will answer with a response to the node who asked "Node 3".
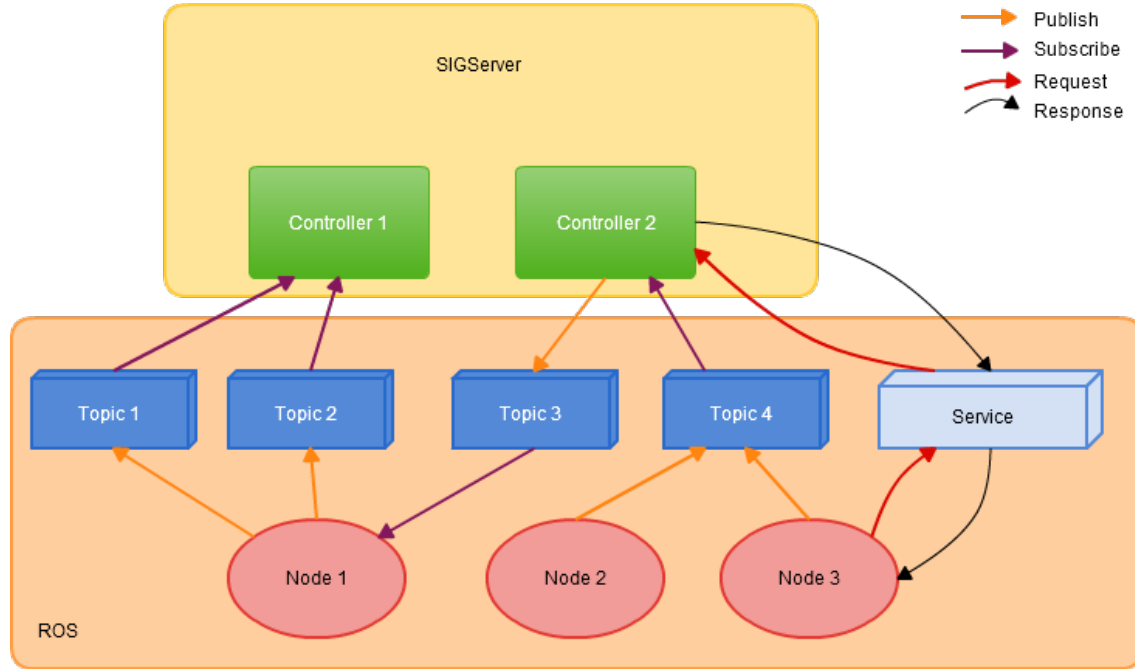
Figure 3.2: Many ROS nodes send and receive information to many controllers

3.2.2 Controllers used

As explained earlier, one "Controller" is associated to one agent for making him act. This association is defined in the xml file which describes the agent.

The same "Controller" can be associated to several agents, that means that all agent associated to this "Controller" will act the same.

On this project, "Controllers" has to be developped for creating topics which sent information and make the agent acting. So, two "Controllers" will be necessary, one for the robot and one for the object. For generals methods like getting entities, they can be included on the object controller.

The best would be a general controller for the methods in common to avoid the duplication of topics, but for this mid-term report, only the robot controller and the object controller are implemented with the methods inside them.

So, in our case, I have as many topics (or services) for getting entities as number of agent in the simulator.

The robot "Controller" inherits from the object "Controller" called "SimObjController". The reason is that in SIGVerse, a robot is an object and has only two methods more than on the object "Controller".

3.2.3   Package

ROS is an open source framework who works with packages, every extension is a package. So, the ROS users just need to download the package wanted.
That is why I choose to develop a package, and only running the node called "ros_controller" will be necessary to launch the SIGServer, create the "Controllers", the topics and services.
We can see figure 3.3 the composition of the package.

src : The generic "Controller" for each kind of agent.

srv : The definition of each services needed.

msg : The definition of each messages needed.

tests : Tests files to check the validity of the implementation.

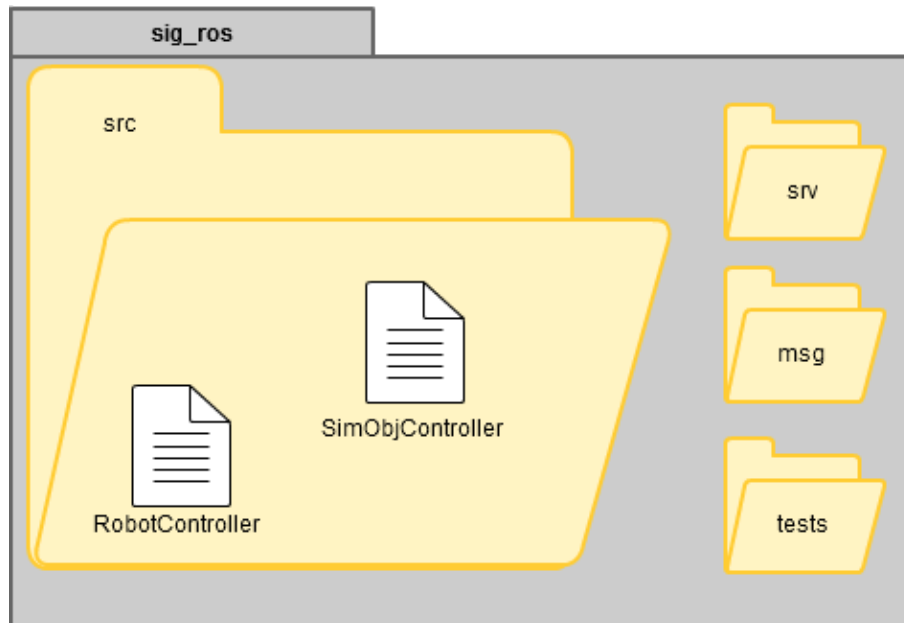Figure 3.3: sig_ros package

3.3   Usage

From the user point of view, three steps are important, see figure 3.4.
First, the user launches the sig_ros package. So, the SIGServer is automatically launched and the SIGViewer can be connected.
Second, the user starts the simulation from the SIGViewer. So, all topics and services are created and linked to the "Controller" thanks to the package sig_ros.

Finally, the user can create all the ROS node he wants and publish and subscribe to the topics and call services created by the step 2.
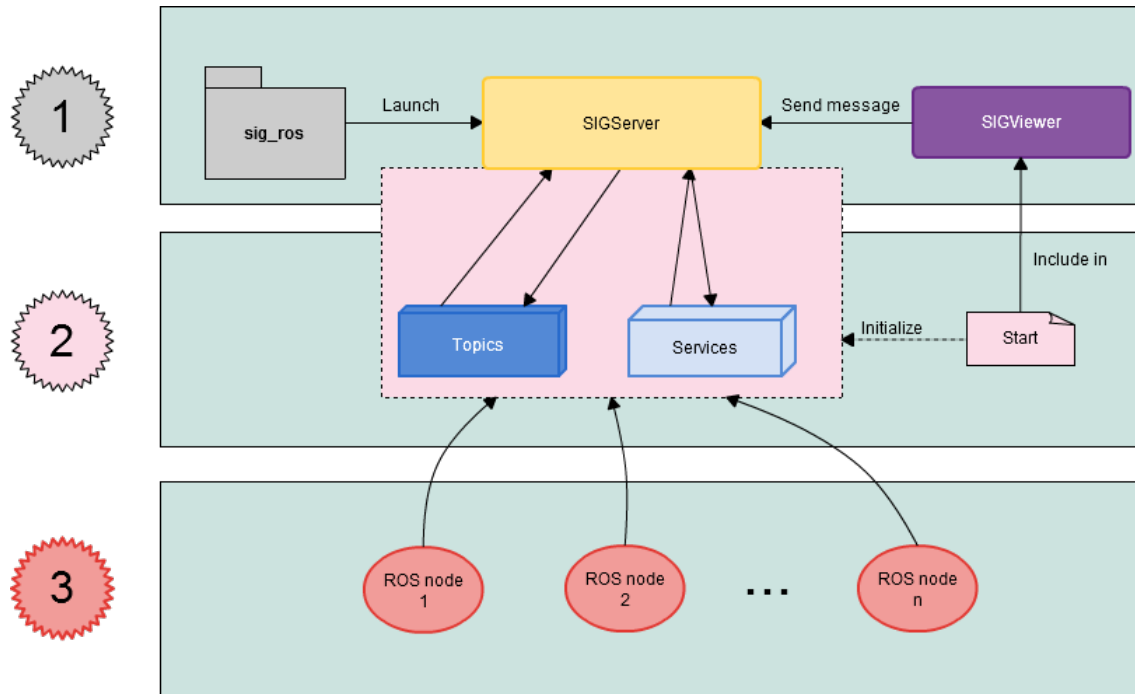
Figure 3.4: Steps to follow to start a simulation with ROS

3.4 Topics & Services

3.4.1 Generalities

Topics and services have to be defined. A node which subscribe to a topic receive the message as soon as it is published to the topic but no answer is given.

On the contrary, the service is a topic but it anwsers to the node who called the service.

The types of messages or service request can be of several simple type (double, string, ...) or a combination of these type or message created by these types.

It is possible to create new types, so the tranfert of SIGVerse object could be possible, but the use of the package has to be as easy as possible. So, the methods needed by the clean up task which return bad type for a message are replaced by a topic or service which execute a group of action, for exemple getPart and getPosition applied to the part are mixed in getPartPosition and the user only has to ask for a part and the position is returned with simple type "double".

The first step is to make the example of the clean up task working, so many topics and services

have been created. Each of them starts by the name of the agent and follow by the name of the topic/service.

Now, we are going to see the topics and services I implemented for the robot agent, but a more exhaustive list with more details is given in annex A.3 and annex A.4. In those annexes, there are the topics for the robot agent but also for the object agent of the clean up task which I have started implementing.

3.4.2 Topics

The list of the topics needed for the robot agent of the clean up task is:

_onRecvMsg : The "Controller" send the message received by the SIGViewer.

_onCollisionMsg : The name of the agent which one is in collision with are sent to this topic. If there is severals collision at the same time, severals messages are sent.

_setWheel : Publish the radius and the distance in a message and they will be applied to the robot.

_setWheelVelocity : Publish the velocity for the left and the right wheel and it will be applied.

_setJointVelocity : set the velocity "angular velocity" to the join called "jointName".

_releaseObj : Publish the part which you want to release an object and it will be done.

The two first topics was obvious, they are the unique topics where the "Controller" publish. Indeed, the dynamic of the "Controller" run two methods when particular events occurs, see section 3.1. That is why, each time it occurs, messages are sent to this topics.

3.4.3 Services

The list of the services needed for the robot agent of the clean up task is:

_get_time : Get the simulation time.

_get_obj_position : Get the position of the object named name, if name is empty, return the position of the agent which the service's name start with.

_get_parts_position : Get the position of the part in parameter.

_get_rotation : Get the quaternion of the agent's rotation.

_get_angle_rotation : Get the angle of the rotation of the agent.

_get_joint_angle : Get the angle between the joint.

_grasp_obj : Grasp the object "obj" with the part "part".

3.5 SIGViewer service

SIGViewer give a graphic interface for the visualization of the world and the robot. But many services can be connected to SIGViewer for example the referee of the Robocup competition.
The connection with the service is made at the SIGViewer level as we can see figure 3.5. The user only has to install the service and add it to the SIGViewer. After that, the interaction with the service from the SIGServer is possible. Indeed, SIGServer is connected to the SIGViewer and the SIGViewer with the service.
Server side, the controller just need to send a message to the SIGViewer to connect with the service. After that, the controller can send every messages wanted to the service.
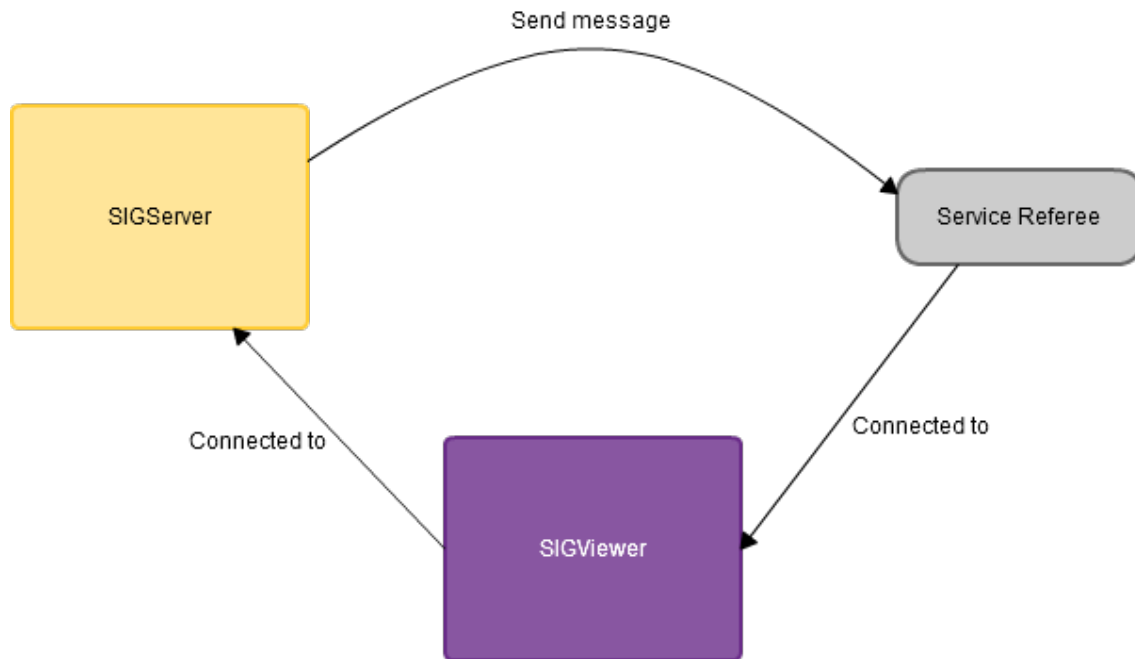

Figure 3.5: Links between SIGServer, SIGViewer and the referee service

Basically, only few methods are related to the SIGViewer service, one for the connection, another for checking the connection and a last one for sending messages to the service. That is why I created two services ros more and one topic. With that, the user can connect all services he wants and interact with them.

3.6 RoboCup Clean up task example

The RoboCup clean up task aim to find the trash, take it and bring it to the good trashbox. We can see an example here `https://www.dropbox.com/sh/wwemhfzyg3rc5c6/AADqz8a0oEoK8hXK6uw1C48_a/SingleCleanUpDemo2014.wmv?dl=0`.
In this demonstration, two trashes are presents and the robot goes to each trash to bring it to a trashbox. Its actions are decided by a script. If a collision occurs points are taken off, if a good things happen points are given.
The count of the score is made by the referee service but a message is sent by a controller called "Moderator" to notify the referee.
The clean up task was the principal use case of the suggested work. We can see at `https://www.youtube.com/watch?v=Fc38tqwr0F0&feature=youtu.be` the result achieved.
We can notice that both videos are similar, that means the principal objective is accomplished.

In this second video, the action of the robot are decided by a script, but this one is one or severals ros nodes who send messages to SIGVerse and get the robot moving as we can see figure 3.6.
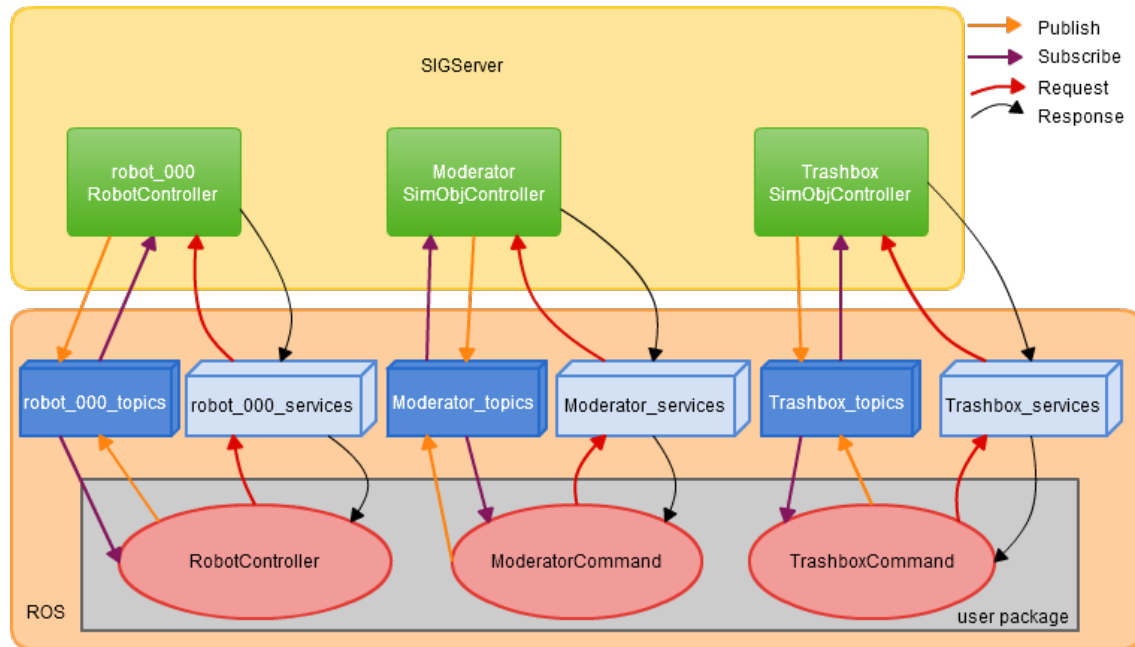

Figure 3.6: Controllers and nodes necessary to the Clean up task

Three "Controller" are generated "robot_000", "Moderator" and "Trashbox", with them the topics and services for each. By default, the name of the topics and services begins by the name of the "Controller".
Each script are inside three nodes: RobotCommand, ModeratorCommand and TrashboxCommand.

It is the user part, he can program everything he wants to send messages to SIGServer. In this case, "ModeratorCommand" connects with the "Referee" service and send it messages, we can see the result on the left top corner in the video.

This is an easy example for the clean up task who can be find on the "user" package provided in the same repository as "sig_ros".

Now, it is necessary to make this package capable of doing every movement for the robot, not only the clean up task. That is why just a mapping of every methods of SIGVerse to manipulate object and robot is necessary.

All topics and services availables are described in annex A.3 and A.4.

A user manual is also available on the sig_ros repository inside the doc folder of the sig_ros package. This manual explains how to use the sig_ros package and the example of the Clean up task.

3.7   ROS package adapation

3.7.1   SLAM

Concept

The node SLAM take as entry two topics, /scan and /tf as we can see figure 3.7. On the /scan topic, the information of the laser scan has to be published there. The type of the message is sensor_msgs/LaserScan and the description can be found on `http://docs.ros.org/api/sensor_msgs/html/msg/LaserScan.html`. The ranges are the values of the distance between the robot and the next obtacle for each angle from angle_min to angle_max separated by angle_increment on the positive way.

The range_min and range_max are respectively the min value and the max value possible for the range.

The intensity is not mandatory, it is the value for the obtacle transparence for the measurement.

The node subscribe to /tf too. /tf provide the tree of the robot from odometry to the laser place. That is why the minimum tree is /odom $\rightarrow$ /base_link. Slam node also need /map $\rightarrow$ /odom but it provides it itself publishing to /tf.

The node publish to two topics and one service is available to get the map.
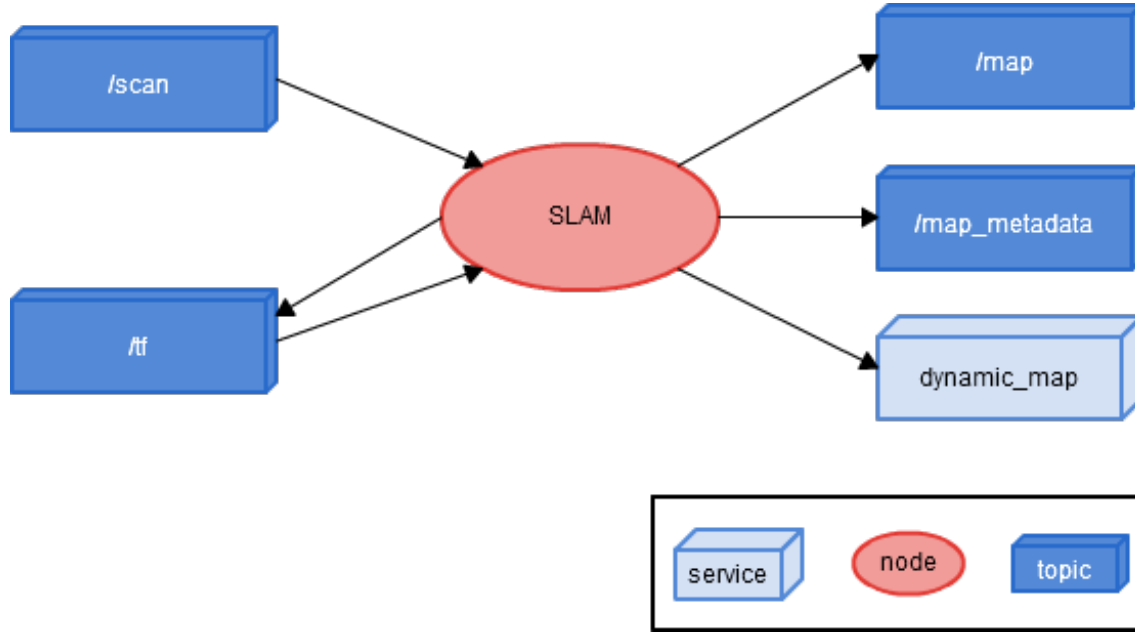
Figure 3.7: SLAM topics and services

Integration into SIGVerse

As we saw section 3.7.1, the topic scan and tf have to be published regularly. That is why the "action" will publish to the topics, because it is always called.
SIGVerse provide a laser scan for its robots, so the data only has to be modified to be on the /scan format. For /tf, it is the same, but the tree has to be built depending on the robot. As the robot can be very different, I chose to build the easiest tree possible and assume that the laser scan is placed at the base_link.

However, many problems occured due to a lack of documentation of the package. Indeed, the ros tutorial to use this package only explains the topics published and subscribed, services availables, parameters, and the type of the messages needed. But nothing about the meaning of the data needed. For example, the field "range" of the scan message has the description "range data [m] (Note: values < range_min or > range_max should be discarded)" but nothing says how the values are taken positive way, negative way, from 0 radian, from 90,...

There is two way to publish a message, publishing directly to a topic or send it by broadcast. /tf has to be sent by broadcast, but nothing informs the user.

Before the integration of this package to SIGVerse, I tried to use it with the turtlebot simulator,

it worked, I could move the turtlebot robot and the map was built. The same has to be done with SIGVerse simulator but no documentation exists about how turtlebot simulator publish information to make the slam package worked.

3.7.2 Inverse kinematics

Concept

ROS provide a package for solving the inverse kinematics and an example is provided on the documentation with a robot called pr2. We can show pr2 with rviz[1] and launch a node from the tutorial to make move the robot in rviz using the inverse kinematics.
With this example, I was able to distinguish three parts of the work to realize, how the inverse kinematics package knows the description of pr2, how the information are sent to the ik package and how the result of the ik package is performed by rviz to make the robot moving.

Robot definition

The ik package need two files, an urdf[2] file to provide the description of the robot or an xacro file who generate the urdf file and a srdf[3] file which describe the semantic of the urdf file.

The SIGVerse robot is not the same as pr2, that is why the construction of an urdf file was necessary. Inside SIGVerse, the robot is described by an xml file which include non-standards x3d[4] files. So, the transformation from x3d to urdf was not a good idea.
The best way was just modifying the urdf file of pr2 to look like the SIGVerse's robot.

The original urdf file had more than 4 000 lines, including "transformation" and gazebo tags. This two kind of tags are used by gazebo to make the robot moving easily, but inside SIGVerse, we do not need it, so the first step was to get rid of this tags.
Then, the urdf file is only made by "link" and "joint" tags. The structure of the file can be see as a tree starting by "base_link" and putting a link between two joints. The origin of the child link of a joint make the length of its. We can see annex A.5, thanks to a tree, the original pr2 structure in the urdf file.
The second step was get rid of everything that the ik package does not need, some joints and links. At the same time, updating the srdf file removing the joints and links who are not necessary. The minimal structure of the robot can be see annex A.6

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[1]rviz is an 3D visualization tool for ROS
[2]Unified Robot Description Format
[3]Semantic Robot Description Format
[4]A royalty-free ISO standard XML-based file format for representing 3D computer graphics

(a) robot_000 inside SIGVerse　　　　　　　(b) robot_000 described by urdf file
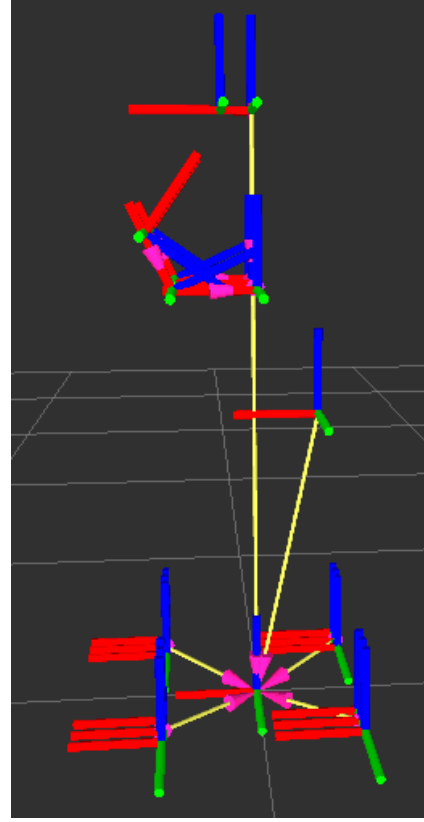
Figure 3.8: Visualisation of robot_000

After that, it was just necessary to modify the size of the robot, height and arm's length related to the joints and links. For that I made a python script who modifies the length of the arms and the size of the robot of the file previously obtained.

Thanks to this script, the urdf file can be generated with the SIGVerse data. The robot can be changed just modifying the xml file for SIGVerse and if the robot has the same structure, the urdf file will be generated and the ik package will work as usual. The unique requirement is that the robot need the same structure.

Once the description file of the SIGVerse robot is built, it just need to fill the variable "robot_description" of the ros launch file with the urdf file and the srdf file to make sure the ik package can access to the robot description.

We can see figure 3.8, the subfigure 3.8a shows the robot in the initial position inside SIGVerse and subfigure 3.8b the same robot described by the urdf file viewed thanks to RViz. The robots have the same proportion but one difference is obvious, the position of the arms is not the same.

A solution to this problem is explained section 3.7.2.

Between these two robots, another difference can be noticed, the orientation of the axis, indeed in SIGVerse y axis is vertical and x and z on the floor whereas in rviz, z is vertical.

Result interpretation

Once the ik package called, it answers a list of numbers corresponding to a list of joints names. The numbers are the angle in radian between the two links of a joint as we can see figure 3.9. We can see the original position of the arm in red (it is the one showed in figure 3.8b), the shoulder to the elbow measures 4 and the elbow to the wrist measures 3.21.

Then, if we ask for the position (0,1,0), the angle for the Elbow' is -0.813847 rad, that is why $\widehat{G, Elbow', Wrist'}$ = -46.63°.

For the shoulder, the angle with the original position and the new one will be -0.27157 rad for the position (0,1,0) and 0.23841 rad for the position (0,-1,0). The shoulder has 0 rad on its original position, indeed, we can see shoulderPan, shoulderLift and Elbow in the same line.
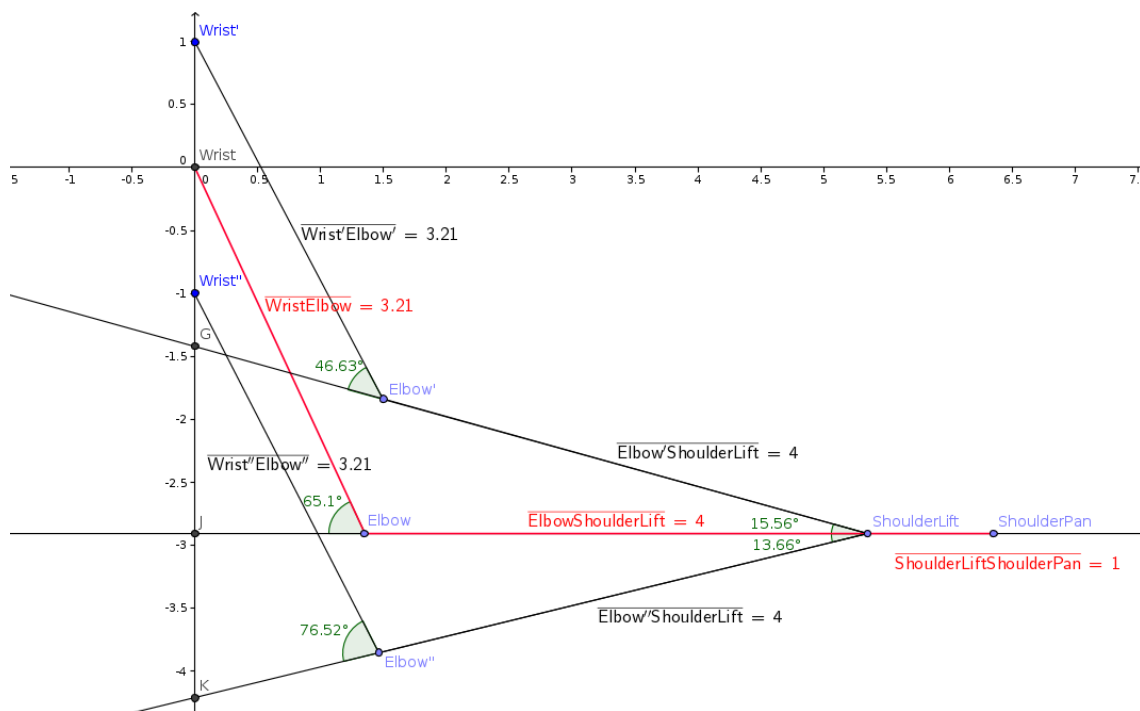

Figure 3.9: Angles between joints

Integration into SIGVerse

The ik package can figure out the position of every joint or not if the position of the end effector can not be reached. That is why I made a service, called "_ik", available to use this

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package. The necessary data are simple, the position of the end effector hoped, the arm (left or right) whom the user wants to move and a last argument to provide the signification of the position.

We can see figure 3.10, the concept for the use of the ik package is the same as a direct interaction with a robot (or object) inside SIGVerse. A service (ik) has to be called and the node RobotController will ask the ik package for the angles of each joints. After that, the RobotController interprets the result and make the arms of the SIGVerse robot moving.
The response by the service is necessary to notify the user node if the move has been possible (and so done) or not.
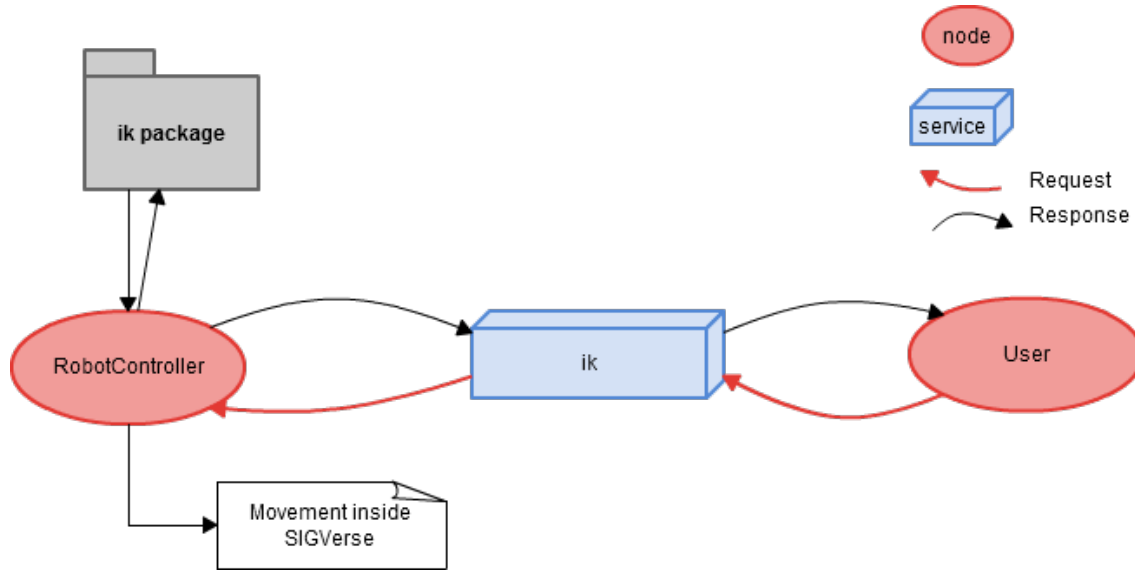
Figure 3.10: Architecture for the use of ik package

The data position can be provided by three different form, absolute, relative or empty.
The empty form corresponds to the vector from the original position (0,0,0) and the new position.
The absolute position corresponds to the coordinates of SIGVerse where the user wants the arm to be.
The relative position corresponds to the vector from the current position to the new position.

The empty position does not need any treatment of the position given but the absolute and relative need to be modifyied. Indeed, the ik package need the data as the "empty" position, example figure 3.9 the position (0,0,0) is the default position.
That is why, it was necessary to know the coordinate of the default position for calculate the vector from the default position to the wanted position. For that, I decided to apply matrix transformation to the arm hands position called "Wrist". See figure 3.11 a visual of the problem.
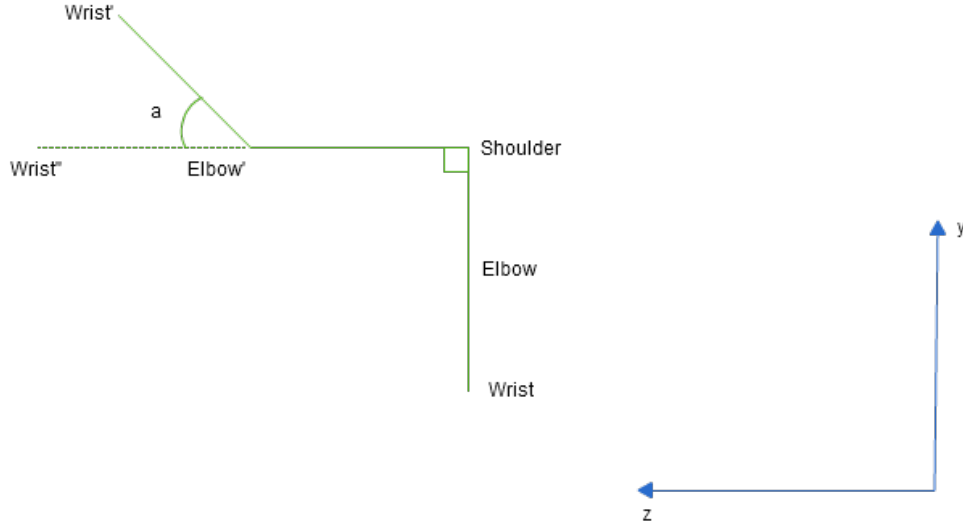
Figure 3.11: Difference between the position of the arm in SIGVerse and RViz

In blue, we can see the axis of SIGVerse. The straight line Shoulder-Elbow-Wrist represents the initial position of the arm inside SIGVerse and the straight lines Shoulder-Elbow'-Wrist' the initial (default) position inside RViz.

The length of each part can be found thanks to SIGVerse and the angle "a" thanks to the ik package. Indeed, if we ask for the position (0,0,0) the angle "a" will be answered.

The computation of the points Elbow' and Wrist" are easy, it is just the translation of the point Shoulder. For the point Wrist', I used matrix of transformation as follow:

Wrist' = $T_{-Elbow'}$ R_{-a} $T_{Elbow'}$ Wrist" with:

$$
T_P = \begin{pmatrix} 1 & 0 & 0 & P_x \\ 0 & 1 & 0 & P_y \\ 0 & 0 & 1 & P_z \\ 0 & 0 & 0 & 1 \end{pmatrix} \text{ and } R_\theta = \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & cos(\theta) & -sin(\theta) & 0 \\ 0 & sin(\theta) & cos(\theta) & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}
$$

This computation is made for both arms. This, allows the user to not having a symetric robot, he can decide of the length of each part independently.

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3.8   Internship progress

3.8.1   Discovery

The first two weeks were dedicated to the installation of the environment: Operating System, Virtual Machine, SIGServer, SIGViewer. After that, I could see how SIGVerse works.

Ones the environment installed, I was able to run examples of the wiki page [1]. With this examples, I could see the function of the "Controller" and then understand how an agent can act, changing places, saying "Hello",... But also, how an agent communicates in both ways, sending and receiving messages.

After installing the environment and learning how to create an agents and make them move, I had to know what was ROS and how it is working. So, I installed all the environment and I did the tutorials of the wiki page [2].
After that, I could run an example of SIGVerse running with ROS and then beginning to investigate how to design an interface between SIGVerse and ROS.

3.8.2   Tools

At the beginning, I was developping on a virtual machine Ubuntu 12.04, but few weeks later SIGVerse was officially available on Ubuntu 14.04, the stablest version where SIGVerse works well. Because of many troubles on Ubuntu 12.04, I decided to upgrade to Ubuntu 14.04.
No IDE[5] is used, only a text editor gedit and a terminal for compilation. ROS and SIGVerse are open source so, I decided to use GitHub.
Because of the reinstallation of the virtual machine, a behaviour was not expected, un keyboard problem, so I decided to change my text editor to vim[6].
I am using Windows 8.1 for the compatibility with the kinect which I could need during the project.

I used Geogebra software to verify my theories about the angles answered by the inverse kinematics package.

I used Cacoo on line to make every schema of this report.

I make unit tests with ROS to be sure of the good functioning.

---

[5]Integrated Development Environment
[6]Visual Interface IMproved

3.8.3 Organisation

The choice of my subject was very open, my supervisor showed me the simulator SIGVerse and the first step after the installation was finding a subject. Because of the short time due to the DoW[7] deadline, I chose to work on this project.

After the three first months, the main part was done, that means the Clean up task demo and the development of topics and services necessary to have a full access to SIGVerse functionnalities from ROS.

After that, I started to add functionnalities to my package. This new functionnalities are an adaptation of the use of a ROS package to SIGVerse. I included the SLAM and inverse kinematics package.

Once a week, all laboratory's members attends a meeting where each members exposes what he planned to do last week, what he actually did and what he will do the next week. I make my own objectives every week for achieving the main goal.

My supervisor answers to my questions and gives me indications during the meeting.

3.8.4 Troubles

Development

First of all, due to my lack of knowledge about ROS, it was very difficult to gain a full view of the project at the beginning. That is why, I had to spend some days to learn from the ROS tutorials and to practice with this framework.

When I started implementing the "Controller", I had a problem of inheritance. Indeed, I had to inherit the robot "Controller" from the object "Controller" and keep this two "Controller" usable for an agent. This inheritance was not easy because of ROS.

I found SIGVerse bug using a function "getSimulationTime()" and others functions. I spent a lot of time diagnosing this bug because I though it came from my code but finally it was a SIGVerse error. So, I made a bug report, sometimes it is just the function who does not answer the good thing, sometimes if we put a wrong arguments, the all simulator can stop.

Documentation

The documentation of SIGVerse is in japanese, so it is quiet difficult to understand what every method does, so I did a lot of tests to figure it out. Fortunately, Google translate can be a good help.

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[7]Description of Work

For the adaptation of the package SLAM and inverse kinematics, we can find a lot of tutorials to use this packages but none of them explains how they works.

For example, we can find turtlebot and a simulator of its. Using the simulator Rviz, we can make the SLAM package works, the data send by turtlebot make possible the computation of the map. If I register the messages sent by turtlebot and then I send it from SIGVerse, it works, but if I make my own messages, it is not working. But no information can be found about this messages, just the structure but not the containt. So, I asked for the help of the community, posting a message on the forum.

For the inverse kinematics package, it is the same problem, there was no information neither the interpretation of the result nor how to set the description of the robot. I figured it out thanks to the examples, trying to understand how it was working.

Conception

The objective of this interface is increasing the number of SIGVerse users by adding ROS users. So, the use of my package has to be instinctive, so the choice of the topics and services has to be relevant.

I made the choice to add an argument to each topics or services called "name", this argument is the same for all of them, that means the object or robot to whom it is applyied.

For the inverse kinematics, I chose to make available three types of position: relative, absolute and respect to the "default" position.

The computation of the default position inside SIGVerse was not easy because of two centimeters less than I had to find. The source of this two centimeters issue was no obvious, it can be because of the robot description, the computation itself or SIGVerse. But this issue is quit important because if the user ask for example for the position (116.64, 85, 42), the inverse kinematics package will answer it not find a solution because the computation of the default position is (116.64, 90, 40) and not (116.64, 90, 42), so my package will ask for the vector (0, -5, 2) instead of (0, -5, 0).

3.8.5   Schedule

What I planned

In the DoW report, I planned to achieve the job L2 before the mid-term report deadline. That means make SIGVerse works with ROS by a simple way like one "Controller" with one node and generate a "Controller" for each agent on the simulator.

After that, I planned to design and develop the topics and services that are necessary to control the agents. I also planned to make an interface between the real human and the simulator. For example, making work the kinect. We can see annex A.2 the schedule of the DoW.

What I actually did

Finally, the first part (before de mid-term report about making work a simple "Controller" with one node) was easier than I though and I could start the next job. So, I started implementing some topics and services for the clean up task before the mid-term report.
Only the methods for the clean up task have been done and some others. You can see at `https://www.youtube.com/watch?v=PL4MCjire2M&feature=youtu.be` a demonstration of the clean up task. The actions of the robot are sent by ROS.

After that, I finished to develop the others topics and services for an all control of the robot. Then, I dealt with the referee during one month.
At this point, a demonstration was possible at a weekly meeting, the video of it is available here `https://www.youtube.com/watch?v=Fc38tqwr0F0&feature=youtu.be`. We can see the robot going for the trash and the referee at the left top corner counting the points.

Then, 3 months left so I decided to make more tests and I found bug on my package and on SIGVerse. After that, I made an adaptation of two ROS package who can provide more functionnalities to SIGVerse.
We can see figure 3.12 the schedule who actually occured.

Reason of the changement

The first changement has been made because it was easier than I though, but then, the second part has been changed because it was more interesting to add functionnalities to SIGVerse than adding the kinect.
Indeed, SLAM and inverse kinematics are two useful tools for every user.

To continue

2015											
March				April				May			June
Week 1	Week 2	Week 3	Week 4	Week 5	Week 6	Week 7	Week 8	Week 9	Week 10	Week 11	Week 12

Planification — Project monitoring

DoW

| Environment installation | Tutorials | DoW Report ◆ | L2:T1 | L2:T2 | L2:T3 | | L3:T1 |

Technical documentation — Technical documentation

Mid-term report

Mid-term Report ◆

June			July				August				
Week 13	Week 14	Week 15	Week 16	Week 17	Week 18	Week 19	Week 20	Week 21	Week 22	Week 23	Week 24

Project monitoring

Final Repo

◆ L3:T2 | L4:T1 | L4:T2 | Final Report ◆

Technical documentation — User documentation

Figure 3.12: Schedule of the internship

4 Conclusion

These two first months of internship make me see a research environment: discovering a new project, finding a subject and designing a solution by myself.
I learnt a lot with the autonomy I had: designing, implementing, testing and finding a solution to the bugs who occured, but also technical skills like C++.

The interface I began to develop has to be functional by the end of the internship. Indeed, ROS users will use my package or may be SIGVerse users who thinks using ROS is an easier way to use SIGVerse. This objective of achievement is very motivated.

For the rest of the internship, many things have to be done, finishing the clean up task, testing, designing and developping the interaction human-SIGVerse.

Bibliography

[1] SIGVerse wiki page : `http://www.sigverse.org/wiki/en/index.php?Tutorial`.

[2] ROS wiki page : `http://wiki.ros.org/fr/ROS/Tutorials`.

[3] SIGVerse wiki page ROS integration tutorial : `http://www.sigverse.org/wiki/en/index.php?ROS%20integration`.

Abstract

I did this internship in the National Institute of Informatics, an inter university research institute which aim to develop the research in multiple domains. But more specifically, in the Inamura lab.

My subject was making an interface between ROS and SIGVerse for growing the SIGVerse community. ROS is a framework for writing robot software and SIGVerse a simulator.

The interface is made in C++ and I tried to make it very easy for the ROS users. Their knowledge about SIGVerse can be very limited or totally inexistant. The ROS users will be able to use SIGVerse as easy as possible. They only have to publish or subscribe topics or to call services that I defined like any ROS package.

This project make me very responsible and independant in the area of software design, need analysis...

J'ai réalisé ce stage dans le laboratoire d'Inamura, au National Institute of Informatics, un institut de recherche dans divers domaines.

Le but de ce projet est de créer une interface entre ROS et SIGVerse afin d'agrandir la communauté de SIGVerse.

ROS est un framework pour le développement de logiciel pour les robots et SIGVerse un simulateur.

L'interface est réalisée en C++ et son utilisation doit être la plus simple possible pour un utilisateur ROS, c'est-à-dire sans ou peu de connaissances de SIGVerse prérequises. Les utilisateurs ROS doivent être capable de communiquer avec SIGVerse sans difficultés, juste en publiant et/ou souscrivant à des "topics" ou appelant des services.

Ce projet m'a permis d'appliquer mes connaissances de manière responsable et autonome dans l'analyse des besoins, conception...

A   Annex

A.1   Jobs

N	Title	Start	End
L1	Management		
T1	Planning	S1	S4
T2	Project monitoring	S5	S24
L2	SIGServer and agents integration		
T1	Run SIGServer from ROS	S5	S5
T2	Generation of one controller associated to one agent	S6	S7
T3	Generation of controller for each agents	S8	S8
L3	Make agents act		
T1	Though Publish/Subscribe	S10	S12
T2	Though ROS Services	S13	S15
L4	Services interface		
T1	Design	S16	S17
T2	Kinect	S18	S20
L5	Documentation		
T1	Technical documentation	S5	S18
T2	User documentation	S19	S23
L6	Report		
T1	Mid-term report	S8	S9
T2	Final report	S22	S24

Table A.1: Jobs

A.2   Schedule

	2015										
	March			April				May			June
Week 1	Week 2	Week 3	Week 4	Week 5	Week 6	Week 7	Week 8	Week 9	Week 10	Week 11	Week 12

Planification | Project monitoring

DoW

Environment installation | Tutorials | DoW Report ◆ | L2:T1 | L2:T2 | L2:T3 | | L3:T1

Technical documentation | Technical documentation

Mid-term report

Mid-term Report ◆

	June			July				August			
Week 13	Week 14	Week 15	Week 16	Week 17	Week 18	Week 19	Week 20	Week 21	Week 22	Week 23	Week 24

Project monitoring

Final Rep

L3:T2 | L4:T1 | L4:T2 | Final Report ◆

Technical documentation | User documentation

A.3 Topics

Topic name	Message	Description
_onRecvMsg	**sender** : string **content** : string	The "Controller" send the message received by the SIGViewer.
_onCollisionMsg	**name** : string **part** : string	The name of the agent which one is in collision with are sent to this topic. If there is severals collision at the same time, severals messages are sent.
_setWheel	**wheelRadius** : double **wheelDistance** : double	Publish the radius and the distance in a message and they will be applied to the robot.
_setWheelVelocity	**leftWheel** : double **rightWheel** : double	Publish the velocity for the left and the right wheel and it will be applied.
_setJointVelocity	**jointName** : string **angularVelocity** : double **max** : double	jointName, angular velocity, max ???
_releaseObj	**arm** : string	Publish the part which you want to release an object and it will be done.
_setAxisAndAngle	**name** : string **axisX** : double **axisY** : double **axisZ** : double **angle** : double	Set the axis defined by "axisX", "axisY" and "axisZ" and set the angle "angle" to the entity called "name", if no name is provided, the main entity of the topic will be set.
_setPosition	**name** : string **posX** : double **posY** : double **posZ** : double	Set the position "posX", "posY" and "posZ" to the entity called "name", if no name is provided, the main entity of the topic will be set.

A.4 Services

Service name	Request	Response	Description
_get_time		**time** : double	Get the simulation time.
_get_obj_position	**name** : string	**posX** : double **posY** : double **posZ** : double	Get the position of the object named name, if name is empty, return the position of the agent which the service's name start with.

_get_parts_position	**part** : string	**posX** : double **posY** : double **posZ** : double	Get the position of the part in parameter.
_get_rotation	**axis** : string	**qW** : double **qX** : double **qY** : double **qZ** : double	Get the rotation of ...
_get_angle_rotation	**axis** : string **x** : double **y** : double **z** : double	**angle** : double	Get the angle of ...
_get_joint_angle	**nameArm** : string	**angle** : double	Get the angle between the joint.
_grasp_obj	**part** : string **obj** : string	**ok** : bool	Grasp the object "obj" with the part "part"
_get_entities	**axis** : string	**entitiesNames** : string[] **length** : int	Get the names of the entities in the simulator.
_check_service	**serviceName** : string	**connected** : bool	Check if the service "serviceName" is connected.
_connect_to_service	**serviceName** : string	**connected** : bool	Connect the "serviceName", true if it is connected, false otherwise.
_get_collision_state _of_main_part		**collisionState** : bool	Get the collision state of the main part.
_is_grasped	**entityName** : string	**answer** : bool	True if "entityName" is grasped, false otherwise. If no entity name is provided, it will return the answer for the agent which is asked

A.5   Pr2 tree
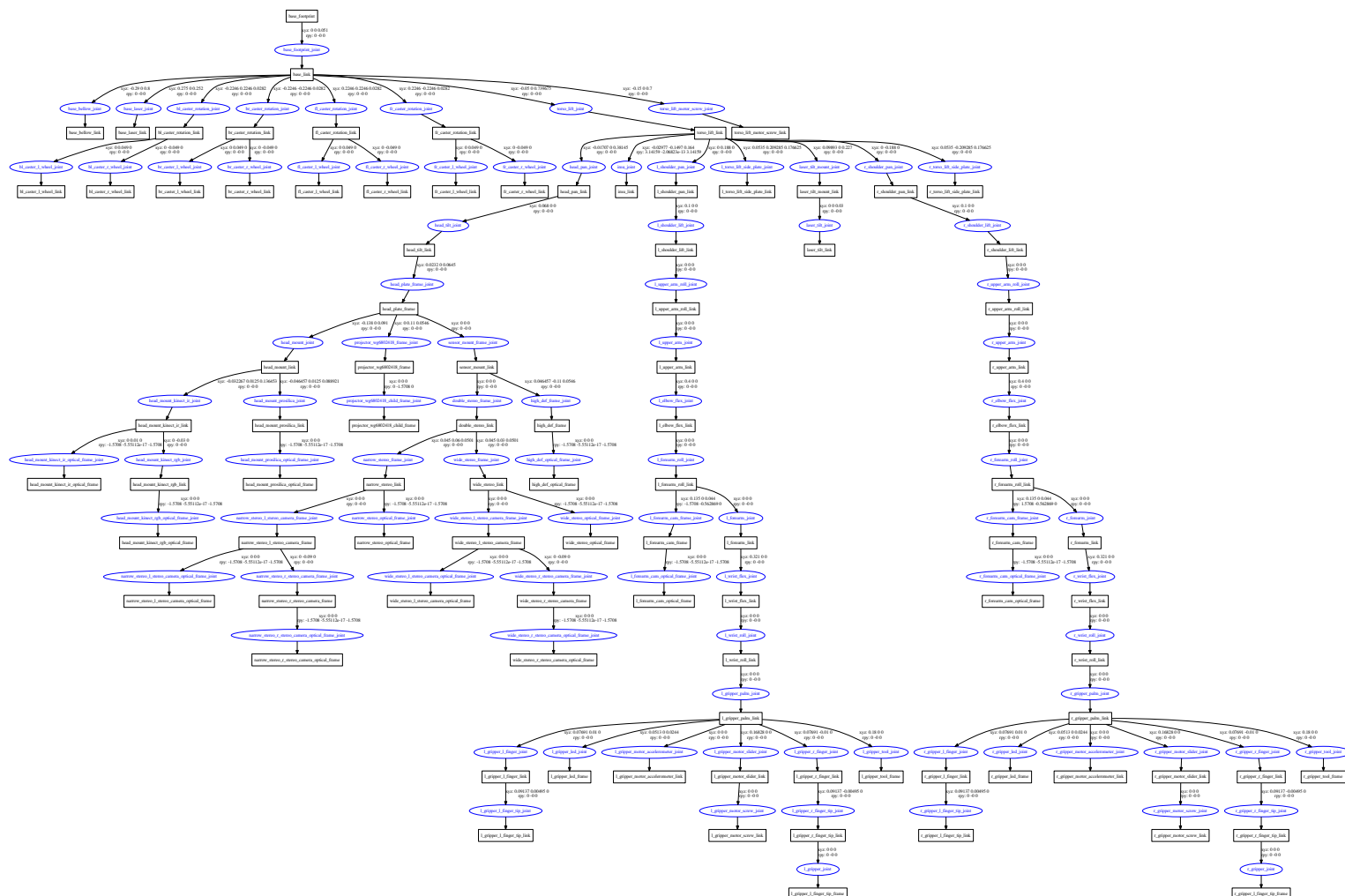
A.6 Minimal structure tree
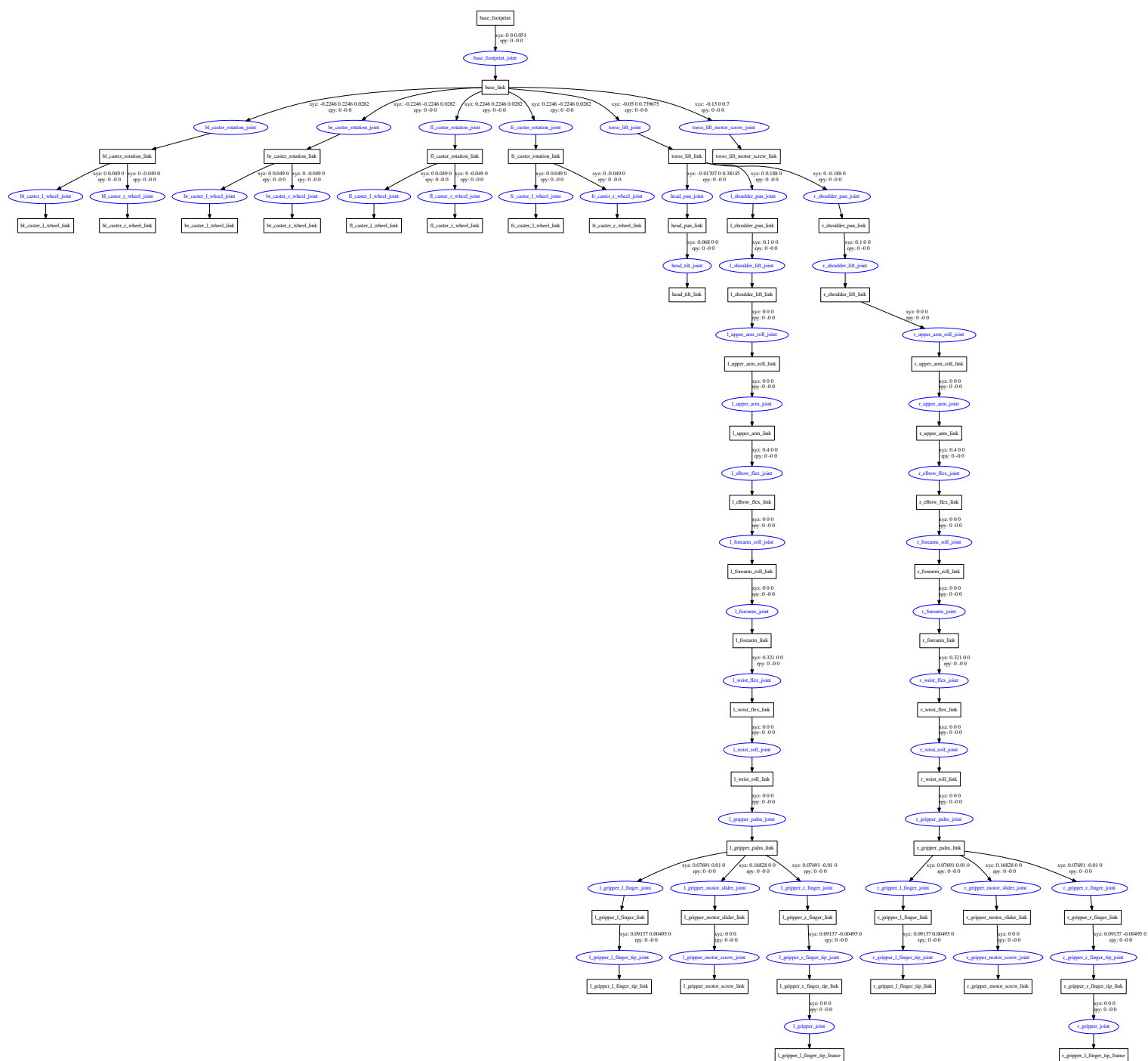
A.7 Position data of SIGVerse for an ik movement

Position asked	Result SIGVerse	Point name	End
0 0 -0.1	116.64 82.82 41.99	B	
0 -0.1 0	116.64 93.83 43.51	C	S4
0 0 0.05	116.64 99.20 41.39	A	S24
0 0.1 0	116.64 93.83 43.50	C..	
0 0.15 0	116.64 93.98 44.83	D	S5
0 -0.1 -0.1	116.64 82.93 43.59	E	S7
0 -0.1 -0.15	116.64 77.59 43.16	F	S8
0 -0.15 -0.1	116.64 83.18 45.33	G	
0 0.1 0.03	116.64 97.05 43.05	H	S24
0 0.16 0	116.64 94.24 44.91	J	S24
0 -0.17 -0.1	116.64 83.56 46.09	K	S24
0 0 -0.08	116.64 85.05 42.13	L	S24
0 0 -0.05	116.64 88.38 42.22	M	S24

Table A.2: Jobs