Note: This tutorials assumes you have read the Introduction to ROS (/ROS/Introduction).

Flease ask about problems and questions regarding this tutorial on ● answers.ros.org (http://answers.ros.org). Don't forget to include in your question the link to this page, the versions of your OS & ROS, and also add appropriate tags.

# Navigating the ROS wiki

**Description:** This tutorial discusses the layout of the ROS wiki (ros.org (/Documentation)) and talks about how to find what you want to know.

Keywords: wiki

Tutorial Level: BEGINNER

**Next Tutorial:** Where Next? (/ROS/Tutorials/WhereNext)

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This tutorial will look at the different headers, links, and sidebars through out the wiki to help you understand how ROS.org is laid out.

#### 1. Basics

### 1.1 ROS.org Landing Page

The landing page is where you are directed to when you type www.ros.org into you browser. Let's look at the ROS wiki header that is displayed at the top of every wiki page.



As you can see each package contains tutorials and troubleshooting specific to the package.

## 1.2 ROS Package Pages

Let's look at *ros-pkg* package wiki page for tf (www.ros.org/wiki/tf) (/tf). The package header for each package is auto generated from the stack and package manifest.

This is the tf package page

tf

This is a list of all packages in the geometry stack

geometry: angles | bullet | eigen | kdl | tf | tf\_conversions

4tf is part of the geometry stack

#### Package Summary

TF is a package that lets the user keep track of multiple coordinate frames over time. TF maintains the relationship between coordinate frames in a tree structure buffered in time, and lets the user transform points, vectors, etc between any two coordinate frames at any desired point in time.

Author: Tully Foote License: BSD

This is the tf package header that is auto generated from the package manifest.xml.

#### Package Links:

Code API Msg/Srv API

**Tutorials** 

**Troubleshooting** 

Reviews (API cleared)

Dependency Tree

The package sidebar contains links to API documentation, tutorials, troubleshooting, and reviews specific to each package.

### 1.3 ROS Stack Pages

Let's look at *ros* stack wiki page for ROS (www.ros.org/wiki/ROS) (/ROS). The stack header for each stack is auto generated from the stack manifest.



This is the ROS stack page

ROS: genmsg\_cpp | gtest | message\_filters | mk | paramiko | pycrypto | rosbagmigration | rosbash | rosbrowse | rosbuild | rosconsole | roscpp | roscreate | rosdep | rosdoc | rosemacs | rosgraph | rosinit | rosjson | roslang | roslaunch | roslib | rosmanual | rosmsg | rosnode | rosout | rospack | rosparam | rospy | rosrecord | rosservice | rostest | rostopic | roswtf | rosdeps | rxtools | std\_msgs | std\_srvs | topic\_tools | wxPython\_swig\_interface | wxswig | xmlrpc++

This is a list of all packages in the ROS stack

### Stack Summary

ROS is an open-source, meta-operating system for your robot. It provides the services you would expect from an operating system, including hardware abstraction, low-level device control, implementation of commonly-used functionality, message-passing between processes, and package management. It also provides tools and libraries for obtaining, building, writing, and running code across multiple computers.

The ROS runtime "graph" is a peer-to-peer network of processes that are loosely coupled using the ROS communication infrastructure. ROS implements several different styles of communication, including synchronous RPC-style communication over Services, asynchronous streaming of data over Topics, and storage of data on a Parameter Server. These are explained in greater detail in our Conceptual Overview.

Author: Eric Berger, Ken Conley, Josh Faust, Tully Foote, Brian Gerkey, Jeremy Leibs,

Morgan Quigley, Rob Wheeler

License: BSD

This is the ROS stack header that is auto generated from the stack manifest.xml.

As you can see each stack contains tutorials and troubleshooting specific to the stack.

#### 2. Advanced

#### Stack Links:

**Tutorials** 

Troubleshooting

Change List

Roadmap

Reviews (unreviewed)

The stack sidebar contains links to tutorials, troubleshooting, change list, roadmap, and reviews specific to each stack.

Beginners can skip this section.

### 2.1 To create tutorial pages under your package

- 1. Once you have created your package page, open the URL with /tutorials at the tail of the URL of your package. For example, suppose your package is located at http://wiki.ros.org/foo\_pkg. You should open http://wiki.ros.org/foo\_pkg/tutorials. This way the wiki will create a new page.
- 2. The page will say This page does not exist yet. What type of page are you trying to create? The wiki is correct, because there's no (hopefully) such page. ROS wiki now shows a list of templates, choose TutorialIndexTemplate.
- 3. Now you are redirected to the wiki page editor. Add whatever change you think you need, and save it at the end. Using Preview often to check how it looks is a great idea. Notice that, however, there are some ROS wiki macros that do not get activated until you save the page (in that case you just have to pray that your edition works, but it's okay to try and error!).

#### 2.1.1 Sort the tutorial

By default, TutorialIndexTemplate uses a macro FullSearchWithDescriptionsCS, which searches all available tutorials under the URL hierarchy you chose (http://wiki.ros.org/foo\_pkg/tutorials in this case). There the order of tutorials are based on the "links" between tutorials (next.0 attribute in each page's tutorial header).

Often, you want to sort the tutorial in your own way, like ROS' basic tutorial top page (/ROS/Tutorials) does. To do so you use TutorialChain macro. See the example in ROS basic tutorials (http://wiki.ros.org/ROS/Tutorials?action=diff&rev2=153&rev1=152).

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