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INFO 802

Master Advanced Mechatronics

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ROS

**ROS message, ROS Service
Lecture 3**

ROS Command Tools

See message definition information:

```
> rosmmsg show [message_type]
```

See active topics:

```
> rostopic list
```

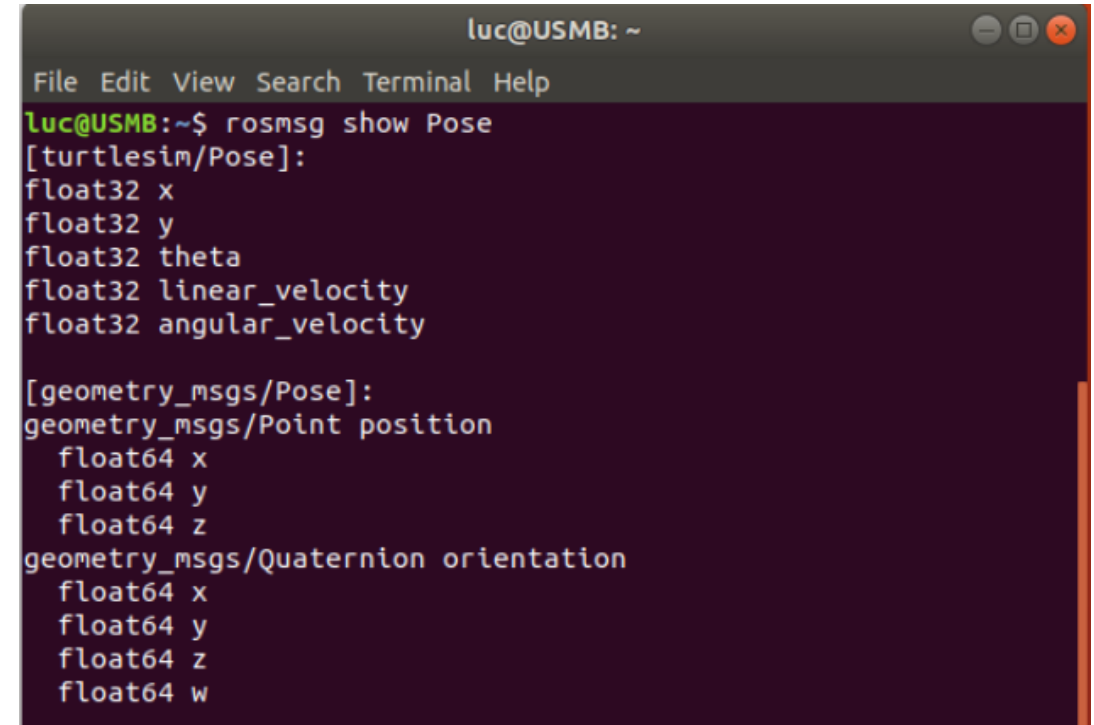
See node information:

```
> rosnode info [message_type]
```

ROS Command Tools

See message definition information:

```
> rosmmsg show [message_type]
```



```
luc@USMB: ~  
File Edit View Search Terminal Help  
luc@USMB:~$ rosmmsg show Pose  
[turtlesim/Pose]:  
float32 x  
float32 y  
float32 theta  
float32 linear_velocity  
float32 angular_velocity  
  
[geometry_msgs/Pose]:  
geometry_msgs/Point position  
  float64 x  
  float64 y  
  float64 z  
geometry_msgs/Quaternion orientation  
  float64 x  
  float64 y  
  float64 z  
  float64 w
```

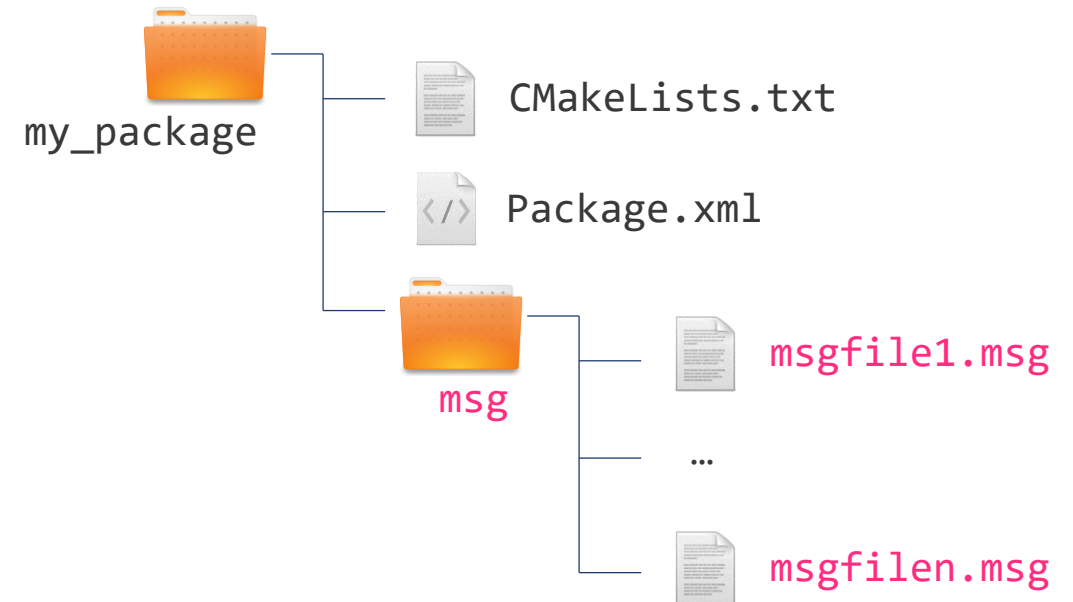
The message of type *Pose* is defined in the package *turtlesim* but also in the package *geometry_msgs* but they are not the same !

ROS Messages

- They are files where we put a specification about the type of data to be transmitted and the values of this data.
- Defined in **.msg* files stored in the msg subdirectory of a package

See message definition information with

```
> rosmmsg show [message_type]
```



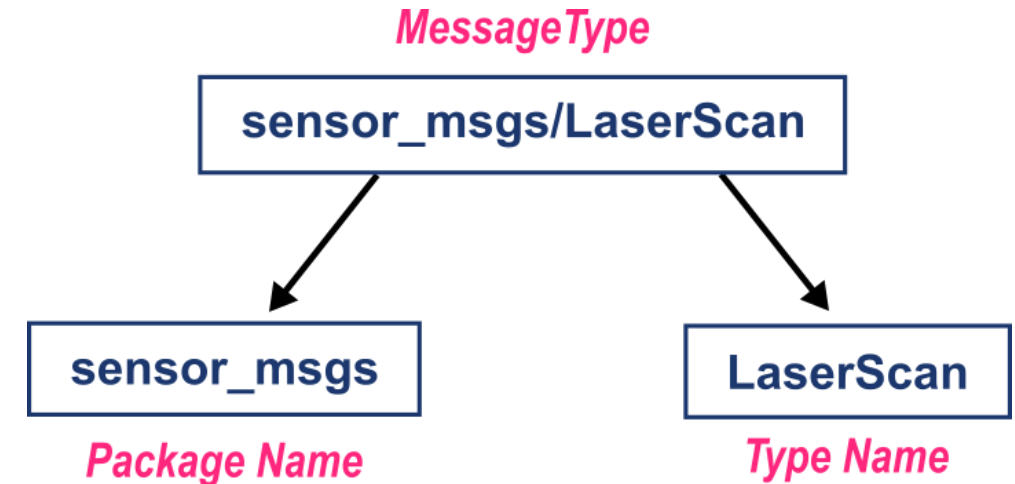
ROS Messages

- Every message type belongs to a specific package

Message type names always contain a slash, and the part before the slash is the name of the containing package:

```
> package_name/type_name
```

Example:



ROS Messages

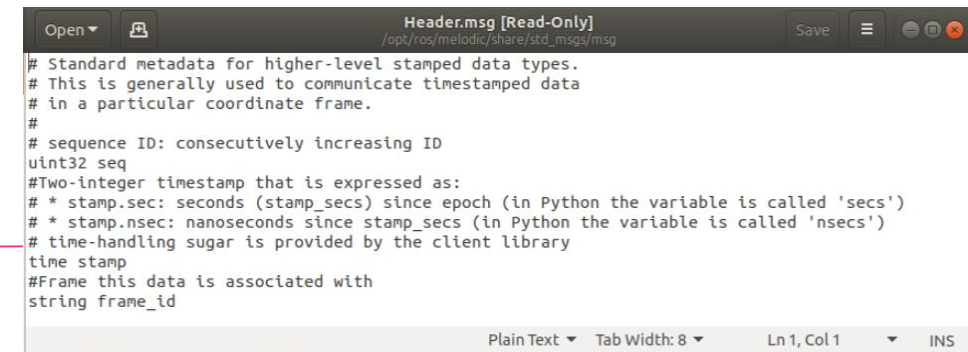
- msgs are just simple text files with a field type and field name per line. The field types you can use are:

- int8, int16, int32, int64 (plus uint*)
- float32, float64
- string
- time, duration
- other msg files
- variable-length array[] and fixed-length array[C]

- Header: special type in ROS

The header contains a timestamp and coordinate frame information that are commonly used in ROS to communicate timestamped data in a particular coordinate frame.

```
uint32 seq
time stamp
string frame_id
```



The screenshot shows a text editor window titled 'Header.msg [Read-Only]' with the file path '/opt/ros/melodic/share/std_msgs/msg'. The content of the file is as follows:

```
# Standard metadata for higher-level stamped data types.
# This is generally used to communicate timestamped data
# in a particular coordinate frame.
#
# sequence ID: consecutively increasing ID
uint32 seq
#Two-integer timestamp that is expressed as:
# * stamp.sec: seconds (stamp_secs) since epoch (in Python the variable is called 'secs')
# * stamp.nsec: nanoseconds since stamp_secs (in Python the variable is called 'nsecs')
# time-handling sugar is provided by the client library
time stamp
#Frame this data is associated with
string frame_id
```

The status bar at the bottom indicates 'Plain Text', 'Tab Width: 8', 'Ln 1, Col 1', and 'INS'.

ROS Messages

- Standard type to use in message

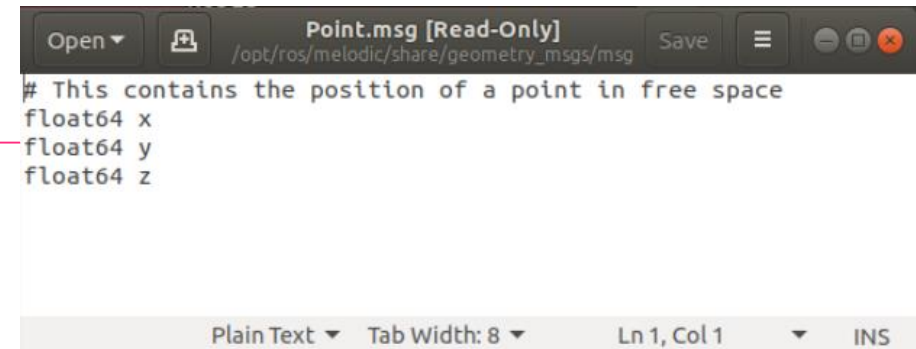
Primitive type	Serialization	C++	Python
bool	Unsigned 8-bit int	uint8_t	bool
int8	Signed 8-bit int	int8_t	int
uint8	Unsigned 8-bit int	uint8_t	int
int16	Signed 16-bit int	int16_t	int
uint16	Unsigned 16-bit int	uint16_t	int
int32	Signed 32-bit int	int32_t	int
uint32	Unsigned 32-bit int	uint32_t	int
int64	Signed 64-bit int	int64_t	long
uint64	Unsigned 64-bit int	uint64_t	long
float32	32-bit IEEE float	float	float
float64	64-bit IEEE float	double	float
string	ASCII string (4-bit)	std::string	string
time	Secs/nsecs signed 32-bit ints	ros::Time	rospy. Time
duration	Secs/nsecs signed 32-bit ints	ros::Duration	rospy. Duration

ROS Messages

- Examples

geometry_msgs/Points.msg

```
float64 x  
float64 y  
float64 z
```



The screenshot shows a text editor window titled "Point.msg [Read-Only]" with the file path "/opt/ros/melodic/share/geometry_msgs/msg". The editor contains the following text: "# This contains the position of a point in free space", "float64 x", "float64 y", and "float64 z". The status bar at the bottom indicates "Plain Text", "Tab Width: 8", "Ln 1, Col 1", and "INS".

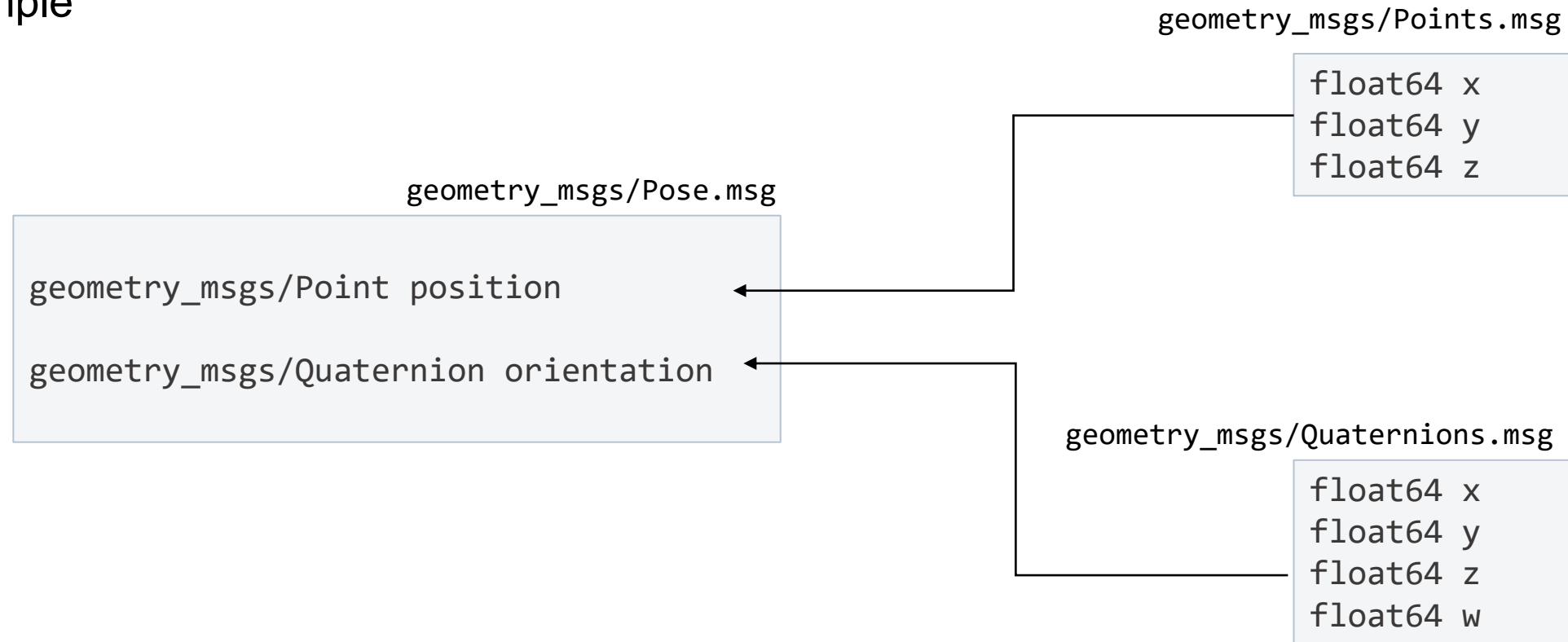
```
# This contains the position of a point in free space  
float64 x  
float64 y  
float64 z
```

geometry_msgs/Quaternions.msg

```
float64 x  
float64 y  
float64 z  
float64 w
```


ROS Messages

- Example



You can use message type from already existing message

How to use ROS Messages in code?

Import the message type from the msg library

Use the message directly with an oriented object way

Use the message with an Object

```
#!/usr/bin/env python
```

```
from geometry_msgs.msg import Pose  
from beginner_tutorials.msg import My_Custom_Message
```

```
# without creating an object  
Pose.position.x = 1.0
```

```
# by creating an object
```

```
My_Object = Pose()  
My_Object.position.x = 1.0
```

```
My_Object.orientation.y = My_Object.position.x + 43.2
```

```
[geometry_msgs/Pose]:  
geometry_msgs/Point position  
float64 x  
float64 y  
float64 z  
geometry_msgs/Quaternion orientation  
float64 x  
float64 y  
float64 z  
float64 w
```

Creating a custom ROS msg

Edit *.msg file

- When Should You Make a New Message Type?

Only when you absolutely have to (check before with *rosmmsg* to see if there is already something there that you can use instead).

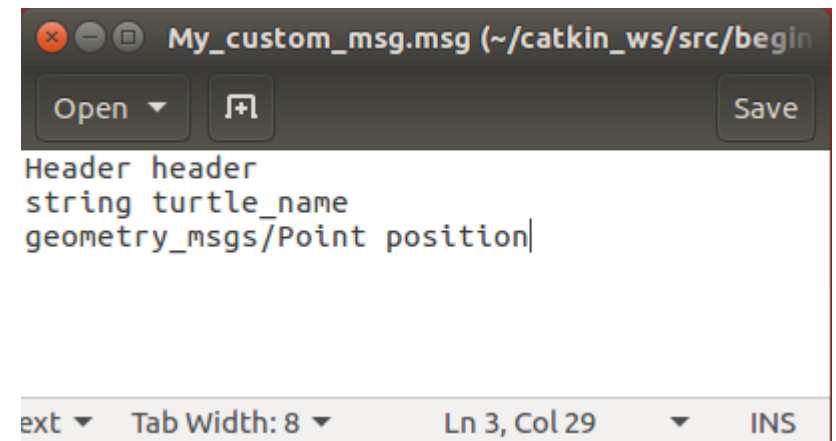
However, there are times when the built-in message types are not enough, and we have to define our own messages

Create a subfolder named **msg** in your package folder

```
> cd ~/catkin_ws/src/beginner_tutorials  
> mkdir msg
```

Create a new **my_custom_msg.msg** file and add the following lines

```
> subl msg/my_custom_msg.msg
```



Creating a custom ROS msg

Modify package.xml file

- We need to make sure that the msg files are turned into source code for C++, Python, and other languages

uncomment those two lines in the package.xml file

```
<build_depend>message_generation</build_depend>  
<run_depend>message_runtime</run_depend>
```

- Note that at build time, we need "message_generation", while at runtime, we need "message_runtime"

Creating a custom ROS msg

Modify CMakefile.txt file

- In CMakeLists.txt add the message_generation dependency to the find package call so that you can generate messages:

```
find_package(catkin REQUIRED COMPONENTS
  roscpp
  rospy
  std_msgs
  message_generation
}
```

- Also make sure you export the message runtime dependency:

```
catkin_package(
#  INCLUDE_DIRS include
#  LIBRARIES multi_sync
    CATKIN_DEPENDS roscpp rospy std_msgs message_runtime
#  DEPENDS system_lib
)
```

Creating a custom ROS msg

Modify CMakefile.txt file

- Find the following block

```
## Generate messages in the 'msg' folder
# add_message_files(
#   FILES
#   Message1.msg
#   Message2.msg
# )
```

- Uncomment it by removing the # symbols and then replace the stand in Message*.msg files with your .msg file, such that it looks like this:

```
add_message_files(
  FILES
  my_custom_msg.msg
)
```

Creating a custom ROS msg

Modify CMakefile.txt file

- ensure the generate_messages() function is called: uncomment this lines

```
# generate_messages(  
#   DEPENDENCIES  
#   std_msgs  
# )
```

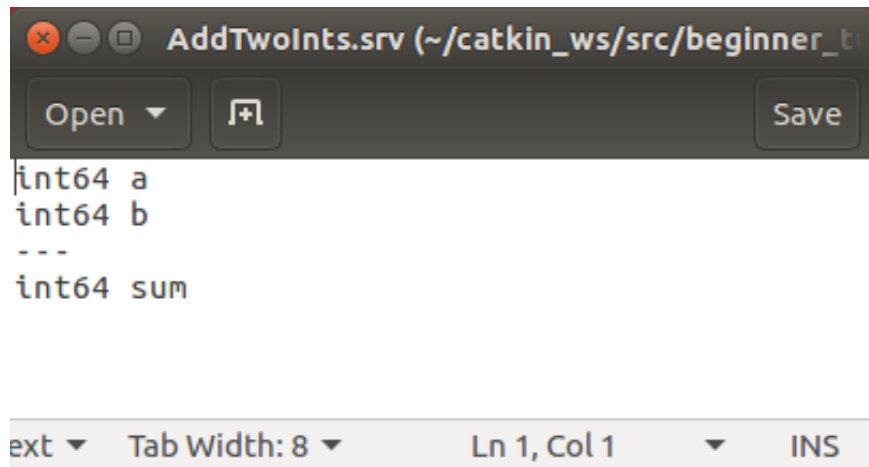
- So it looks like:

```
generate_messages(  
  DEPENDENCIES  
  std_msgs  
)
```

cmake will then know that the project needs to be reconfigured with the addition of msg files

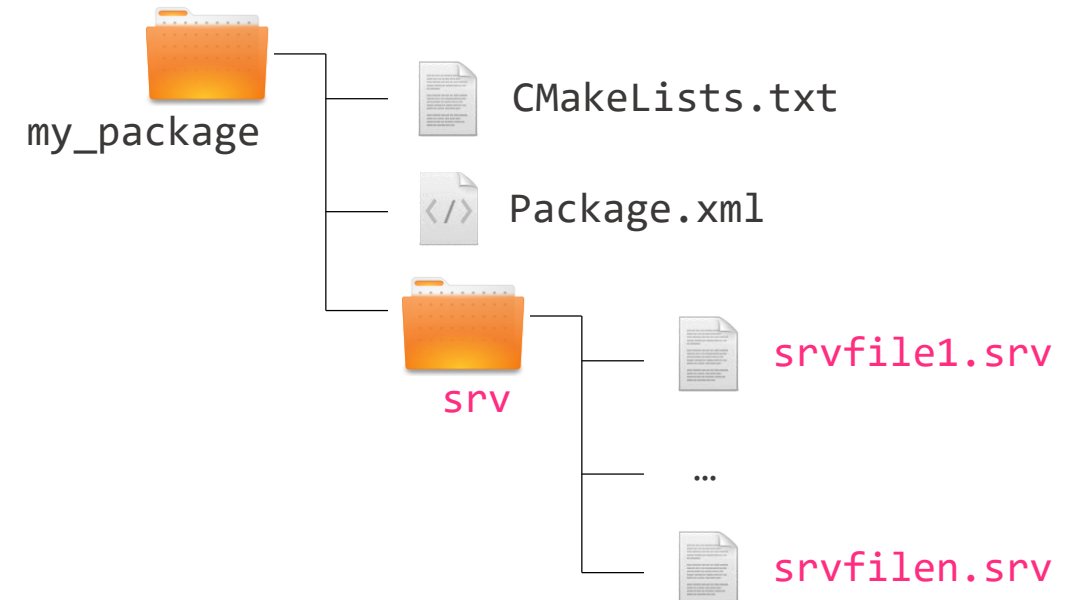
Creating a ROS srv

- Defined in `*.srv` files stored in the `srv` subdirectory of a package
- `srv` files are just like `msg` files, except they contain two parts: a request and a response. The two parts are separated by a `'---'` line.



```
int64 a
int64 b
---
int64 sum
```

ext Tab Width: 8 Ln 1, Col 1 INS



Creating a ROS srv

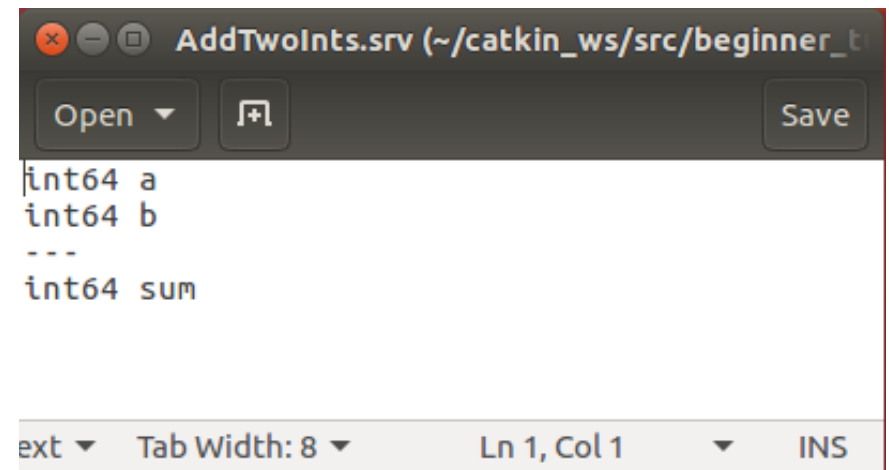
Modify package.xml file

Create a subfolder named **srv** in your package folder

```
> cd ~/catkin_ws/src/beginner_tutorials  
> mkdir srv
```

Example: create `AddTwoInts.srv` file and add the following lines

```
> subl srv/AddTwoInts.srv
```



The screenshot shows a text editor window titled "AddTwoInts.srv (~/.catkin_ws/src/beginner_tutorials)". The window has a menu bar with "Open" and "Save" buttons. The text content is as follows:

```
int64 a  
int64 b  
---  
int64 sum
```

The status bar at the bottom indicates "ext", "Tab Width: 8", "Ln 1, Col 1", and "INS".

Creating a ROS srv

Modify package.xml file

- We need to make sure that the srv files are turned into source code for C++, Python, and other languages

uncomment those two lines in the package.xml file

```
<build_depend>message_generation</build_depend>  
<run_depend>message_runtime</run_depend>
```

- Note that at build time, we need "message_generation", while at runtime, we need "message_runtime"

Creating a ROS srv

Modify CMakefile.txt file

- In CMakeLists.txt add the message_generation dependency to the find package call so that you can generate messages:

(Despite its name, message_generation works for both msg and srv.)

```
find_package(catkin REQUIRED COMPONENTS
  roscpp
  rospy
  std_msgs
  message_generation
}
```

Creating a ROS srv

Modify CMakefile.txt file

- Find the following block

```
## Generate messages in the 'msg' folder
# add_service_files(
#   FILES
#   Service1.msg
#   Service2.msg
# )
```

- Uncomment it by removing the # symbols and then replace the stand in Service*.msg files with your .srv file, such that it looks like this:

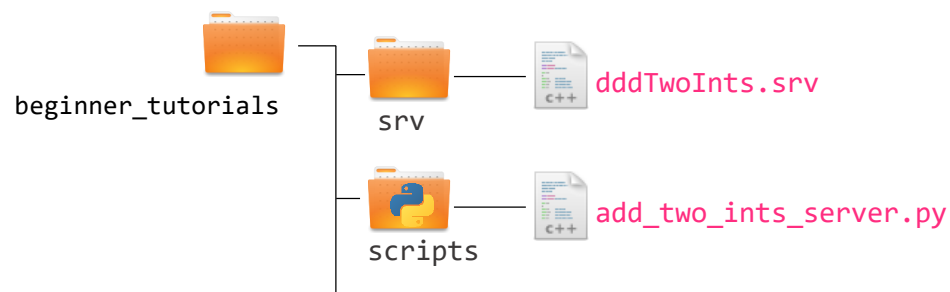
```
add_service_files(
  FILES
  AddTwoInts.srv
)
```

Creating a Service and Client Node (Python)

Writing the **Service** Node

Edit a py file in scripts folder

```
> cd ~/catkin_ws/beginner_tutorials/src/scripts  
> sudo subl Add_two_ints_server.py
```



... and make it executable

```
> sudo chmod +x scripts/add_two_ints_server.py
```

```
#!/usr/bin/env python

from beginner_tutorials.srv import *
import rospy

def handle_add_two_ints(req):
    print "Returning [%s + %s = %s]"%(req.a, req.b, (req.a + req.b))
    return AddTwoIntsResponse(req.a + req.b)

def add_two_ints_server():
    rospy.init_node('add_two_ints_server')
    s = rospy.Service('add_two_ints', AddTwoInts,
    handle_add_two_ints)
    print "Ready to add two ints."
    rospy.spin()

if __name__ == "__main__":
    add_two_ints_server()
```

Creating a Service and Client Node (Python)

Examining the **Service** Node

The *service* file has been defined and is located in the *srv* folder

init_node(): declare the node

This declares a new service named *add_two_ints* with the *AddTwoInts* service type. All requests are passed to *handle_add_two_ints* function. *handle_add_two_ints* is called with instances of *AddTwoIntsRequest* and returns instances of *AddTwoIntsResponse*.

```
#!/usr/bin/env python

from beginner_tutorials.srv import *
import rospy

def handle_add_two_ints(req):
    print "Returning [%s + %s = %s]"%(req.a, req.b, (req.a + req.b))
    return AddTwoIntsResponse(req.a + req.b)

def add_two_ints_server():
    rospy.init_node('add_two_ints_server')
    s = rospy.Service('add_two_ints', AddTwoInts, handle_add_two_ints)
    print "Ready to add two ints."
    rospy.spin()

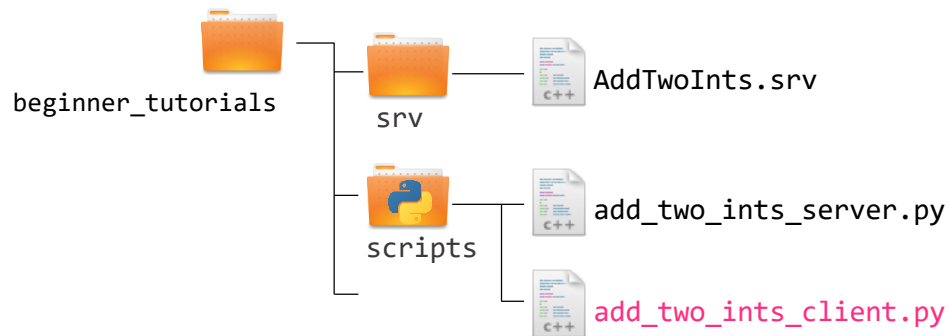
if __name__ == "__main__":
    add_two_ints_server()
```

Creating a Service and Client Node (Python)

Writing the Client Node

Edit a py file in scripts folder

```
> cd ~/catkin_ws/beginner_tutorials/src/scripts  
> sudo subl Add_two_ints_client.py
```



... and make it executable

```
> sudo chmod +x scripts/Add_two_ints_client.py
```

```
#!/usr/bin/env python

import sys
import rospy
from beginner_tutorials.srv import *

def add_two_ints_client(x, y):
    rospy.wait_for_service('add_two_ints')
    try:
        add_two_ints = rospy.ServiceProxy('add_two_ints', AddTwoInts)
        resp1 = add_two_ints(x, y)
        return resp1.sum
    except rospy.ServiceException, e:
        print "Service call failed: %s"%e

def usage():
    return "%s [x y]"%sys.argv[0]

if __name__ == "__main__":
    if len(sys.argv) == 3:
        x = int(sys.argv[1])
        y = int(sys.argv[2])
    else:
        print usage()
        sys.exit(1)
    print "Requesting %s+%s"%(x, y)
    print "%s + %s = %s"%(x, y, add_two_ints_client(x, y))
```

Creating a Service and Client Node (Python)

Examining the Client Node

Wait for the service named `add_two_ints` to be advertised by the server

Once the service is advertised, we can set up a local proxy for it

```
#!/usr/bin/env python

import sys
import rospy
from beginner_tutorials.srv import *

def add_two_ints_client(x, y):
    rospy.wait_for_service('add_two_ints')
    try:
        add_two_ints = rospy.ServiceProxy('add_two_ints', AddTwoInts)
        resp1 = add_two_ints(x, y)
        return resp1.sum
    except rospy.ServiceException, e:
        print "Service call failed: %s"%e

def usage():
    return "%s [x y]"%sys.argv[0]

if __name__ == "__main__":
    if len(sys.argv) == 3:
        x = int(sys.argv[1])
        y = int(sys.argv[2])
    else:
        print usage()
        sys.exit(1)
    print "Requesting %s+%s"%(x, y)
    print "%s + %s = %s"%(x, y, add_two_ints_client(x, y))
```


Creating a Publisher and a Subscriber Node (Python)

Building the nodes

If not done yet: make the node executable (for Python only)

```
> subl chmod +x scripts/add_two_ints_server.py  
> subl chmod +x scripts/add_two_ints_client.py
```

Build package

(we use Cmake as the build system even for Python nodes)

```
> cd ~/catkin_ws  
> catkin_make beginner_tutorials
```

Make sure you have sourced your workspace's setup.bash file

```
> source ~/catkin_ws/devel/setup.bash
```

ROS Bags

- **rosvbag**: set of tools for recording messages and playing back later to ROS topics offline.
- Can be used to mimic real sensor streams for offline debugging.
- Useful for debugging algorithm.
- The file a name is in the format: *file_name_YYYY-MM-DD-HH-mm-ss.bag*

Record topics with

```
> rosvbag record [topic_1] [topic_2] -o [bag_name]
```

Playback messages with

```
> rosvbag play [bag_name]
```

Examples

```
> rosvbag record -a
```

```
> rosvbag play --clock mybag.bag
```

```
luc@luc: ~/catkin_ws/bagfiles
luc@luc:~/catkin_ws/bagfiles$ rosvbag info 2019-03-07-18-03-41.bag
path:      2019-03-07-18-03-41.bag
version:   2.0
duration:  32.5s
start:     Mar 07 2019 18:03:41.15 (1551978221.15)
end:       Mar 07 2019 18:04:13.63 (1551978253.63)
size:      294.7 KB
messages:  4111
compression: none [1/1 chunks]
types:     geometry_msgs/Twist [9f195f881246fdfa2798d1d3eebca84a]
           rosvgraph_msgs/Log  [acffd30cd6b6de30f120938c17c593fb]
           turtlesim/Color      [353891e354491c51aabe32df673fb446]
           turtlesim/Pose       [863b248d5016ca62ea2e895ae5265cf9]
topics:    /rosout              4 msgs      : rosvgraph_msgs/Log
           /turtle1/cmd_vel      70 msgs      : geometry_msgs/Twist
           /turtle1/color_sensor 2022 msgs     : turtlesim/Color
           /turtle1/pose         2015 msgs     : turtlesim/Pose
```

Example logging *turtlesim*

```
roscore http://USMB:11311/
```

```
PARAMETERS
```

```
* /rostdistro: kinetic  
* /rosversion: 1.12.14
```

```
NODES
```

```
auto-starting new master  
process[master]: started with pid [11443]  
ROS_MASTER_URI=http://USMB:11311/  
  
setting /run_id to cfd74b78-41a4-11e9-b61e-08002711f8f  
process[rosout-1]: started with pid [11456]  
started core service [/rosout]  
□
```

```
luc@USMB: ~  
luc@USMB:~$ rosrunc turtlesim turtle_teleop_key  
Reading from keyboard  
-----  
Use arrow keys to move the turtle.  
□
```

```
luc@USMB: ~  
luc@USMB:~$ □
```

```
luc@USMB: ~
```

```
luc@USMB:~$ rosrunc turtlesim turtlesim_node  
[rospack] Error: package 'turtlesim' not found  
luc@USMB:~$ rosrunc turtlesim turtlesim_node  
[ INFO] [1552051226.777712214]: Starting turtlesim with node name  
/turtlesim  
[ INFO] [1552051226.789758992]: Spawning turtle [turtle1] at x=[5  
544445], y=[5,544445], theta=[0,000000]  
□
```

TurtleSim



ROS computation graph *rqt*

- *rqt_graph* creates a dynamic graph of what's going on in the system
- *rqt_console* attaches to ROS's logging framework to display output from nodes. *rqt_logger_level* allows us to change the verbosity level (DEBUG, WARN, INFO, and ERROR) of nodes as they run.
- Prerequisite: Install rqt package

```
> sudo apt-get install ros-melodic-rqt ros-melodic-rqt-common-plugins
```

Launch *rqt_console*

```
> rosrun rqt_console rqt_console
```

Launch *roslaunch rqt_logger_level rqt_logger_level* (in an other terminal)

```
> rosrun rqt_logger_level rqt_logger_level
```

ROS computation graph *rqt*

Visualize running topics and nodes

```
> rosrun rqt_graph rqt_graph
```

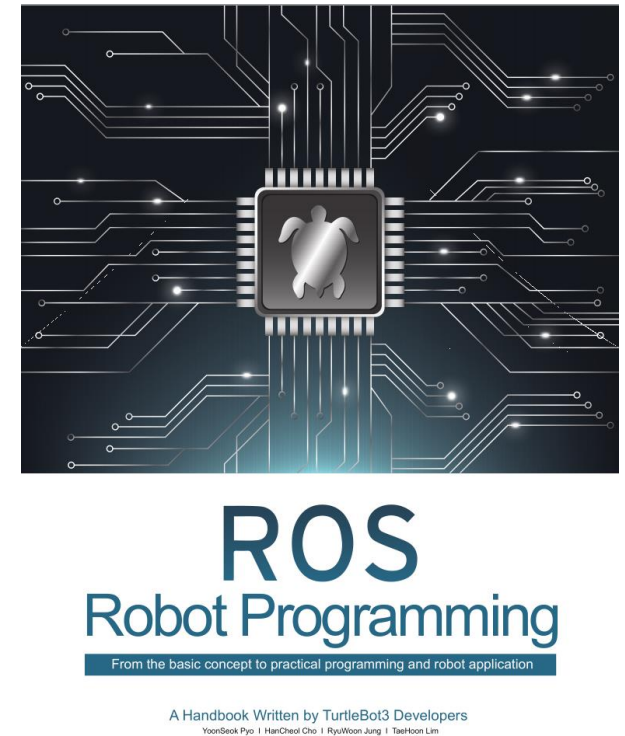
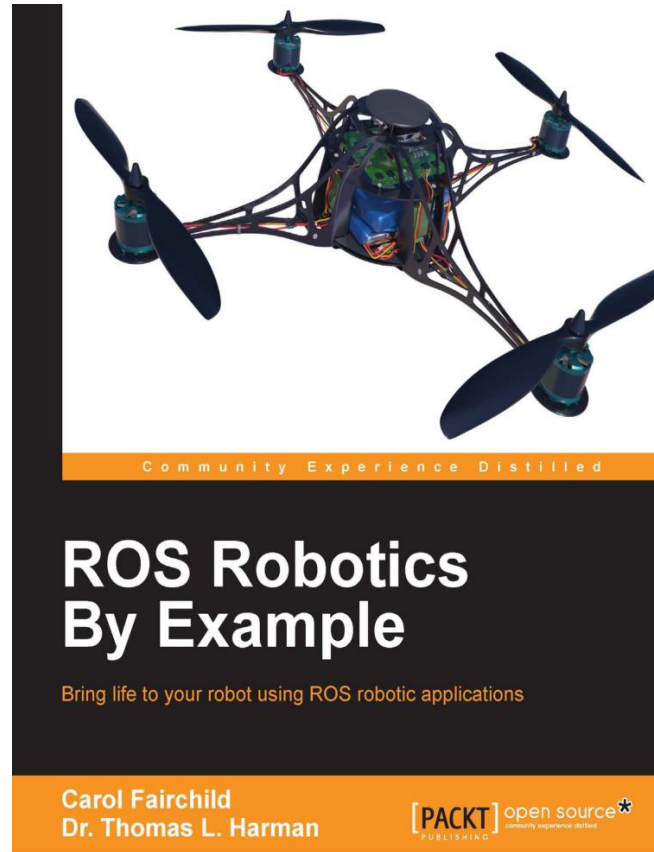
Visualize running topics and nodes

```
> rosrun rqt_plot rqt_plot
```

Further References

- **ROS Wiki**
 - <http://wiki.ros.org/>
- **Installation**
 - <http://wiki.ros.org/ROS/Installation>
- **Tutorials**
 - <http://wiki.ros.org/ROS/Tutorials>
- **Available packages**
 - <http://www.ros.org/browse/>
- **ROS Cheat Sheet**
 - <https://www.clearpathrobotics.com/ros-robot-operating-system-cheat-sheet/>
 - https://kapeli.com/cheat_sheets/ROS.docset/
- **ROS Best Practices**
 - https://github.com/leggedrobotics/ros_best_practices/wiki
- **ROS Package Template**
 - https://github.com/leggedrobotics/ros_best_practices/tree/master/ros_package_template

Relevant books



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SYMME