ROS Workshop

Prequisites

- Text editor VScode (not sponsored)
- Terminal emulator Depends on your OS
- Docker installation

Why TERMINAL?



Basic Terminal Navigation

File Navigation

- 1s: List directory contents.
- cd : Change directory.
- pwd : Print working directory path.

File Management

- mkdir: Create new directories.
- touch: Create new empty files.
- cp : Copy files or directories.
- mv : Move or rename files or directories.
- rm: Remove files or directories (use with caution).

Viewing and Editing Files

- cat: Display file contents.
- nano or vim: Basic text editors within the terminal.

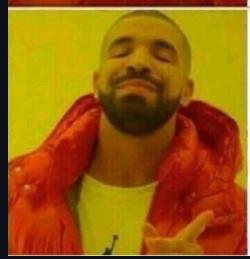
Tips and Tricks

- Tab Completion: Quickly complete commands or file names.
- Command History: Use the up/down arrow keys to navigate through previous commands.
- Wildcards: Utilize * and ? for pattern matching.

USING COMMANDLINE



TYPING SIMPLE 10 CHARARACTER COMMAND OKNOW BY HEARTH



PRESSING ARROWUP 10000111118

What is docker?



Containerisation

- Think of a container as a lightweight, portable box that contains everything an application needs to run.
- It includes the application code, runtime, system tools, libraries, and settings.

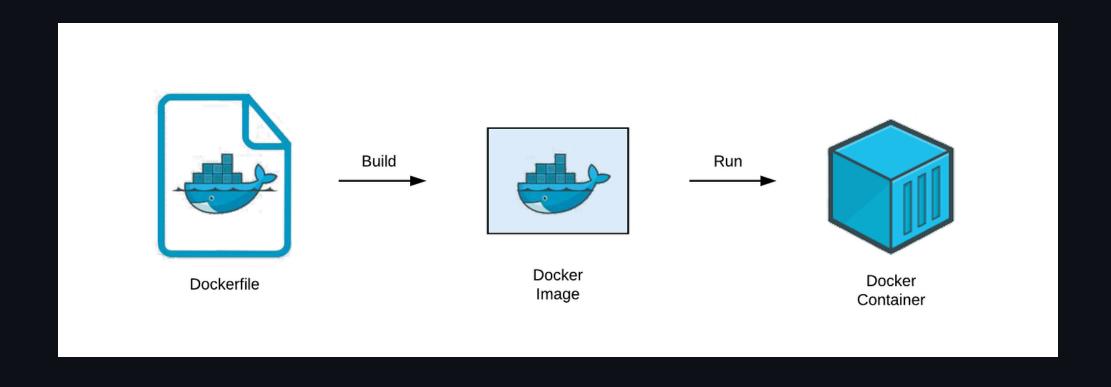


Why docker?

- gives you the ability to run a program on any given machine with docker without dependency issues and conflicts
 - * additional usecase scale apps over multiple server

Docker for robotics ??

How does it work?



Dockerfile

- A text file with instructions on how to build a Docker image.
- It's like a recipe for creating your container environment.

Docker Image

- A snapshot of a container's file system.
- Built from a Dockerfile.
- Immutable and can be shared.

Docker Container

- A running instance of a Docker image.
- Isolated and has its own filesystem, network, and process space.

Acessing your container through VS code

Basic Docker Commands

Image Management

- docker pull: Download images from a registry.
- docker images: List downloaded images.

Container Management

- docker run: Create and start a container.
 - © Example: docker run -it ubuntu:latest /bin/bash
- docker ps : List running containers.
- docker stop: Stop a running container.
- docker rm: Remove stopped containers.

Interacting with Containers

- docker exec : Run commands in a running container.
 - © Example: docker exec -it [container_id] /bin/bash
- docker cp: Copy files between host and container.
 - © Example: docker cp [container_id]:/path/to/file /host/path

```
#!/bin/sh
container_name=f1tenth_gym_ros
create container (){
    docker run --rm -it\
    --name ${container name} \
    -h ${container_name} \
    --env="DISPLAY" \
    --env="QT X11 NO MITSHM=1" \
    --volume="/tmp/.X11-unix:/tmp/.X11-unix:rw" \
    -v $(pwd)/sim_ws:/sim_ws \
    f1tenth:gym_ros_foxy \
    run sim.sh
rm_container (){
        if [ "$(docker ps -aq -f name=${container_name})" ]
               if [ "$(docker ps -aq -f status=running -f name=${container name})" ]
                then
                        docker stop ${container_name}
                fi
               docker rm ${container name}
        fi
if [ "$(docker ps -aq -f status=running -f name=${container_name})" ]
then
        echo "Container is Running. Starting new session."
        docker exec -it ${container_name} bash
else
        rm_container
        xhost + local:host
        create_container
        xhost - local:host
fi
```

```
FROM ros:foxy # Defines which base image youll use
SHELL ["/bin/bash", "-c"]
# dependencies
RUN apt-get update --fix-missing && \
   apt-get install -y git \
                      neovim \
                      python3-pip \
                      libeigen3-dev \
                     tmux \
               ros-foxy-rviz2
RUN apt-get -y dist-upgrade
RUN pip3 install transforms3d
# f1tenth gym (downloads the code for f1tenth gym)
RUN git clone https://github.com/f1tenth/f1tenth gym
RUN cd f1tenth gym && \
   pip3 install -e .
# ros2 gym bridge (downloads the code ros2 gym bridge)
RUN mkdir -p sim_ws/src/
RUN cd sim_ws/src && \
   git clone https://github.com/f1tenth/f1tenth_gym_ros.git
RUN source /opt/ros/foxy/setup.bash && \
   cd sim_ws &&\
   apt-get update --fix-missing && \
   rosdep install -i --from-path src --rosdistro foxy -y && \
   colcon build
RUN printf \
source /opt/ros/foxy/setup.bash \n \
source /sim ws/install/setup.bash \n " \
>> /root/.bashrc
RUN touch run sim.sh
RUN chmod +x run_sim.sh
RUN printf \
"#!/bin/bash \n \
source /opt/ros/foxy/setup.bash \n \
source /sim ws/install/setup.bash \n \
cd /sim_ws && colcon build \n \
ros2 launch f1tenth_gym_ros gym_bridge_launch.py" \
>> run_sim.sh
#change map
RUN cd /sim ws && \
sed -i 's/levine/Spielberg_map/g' /sim_ws/src/f1tenth_gym_ros/config/sim.yaml && \
colcon build # ros specific command, youll learn it later
ENTRYPOINT ["/bin/bash"]
```

• Explains key concepts (fast!)

100+ Docker Concepts you Need to Know (youtube.com)

• CLI Cheat Sheet

docker_cheatsheet.pdf

