



Software Lecture 3:

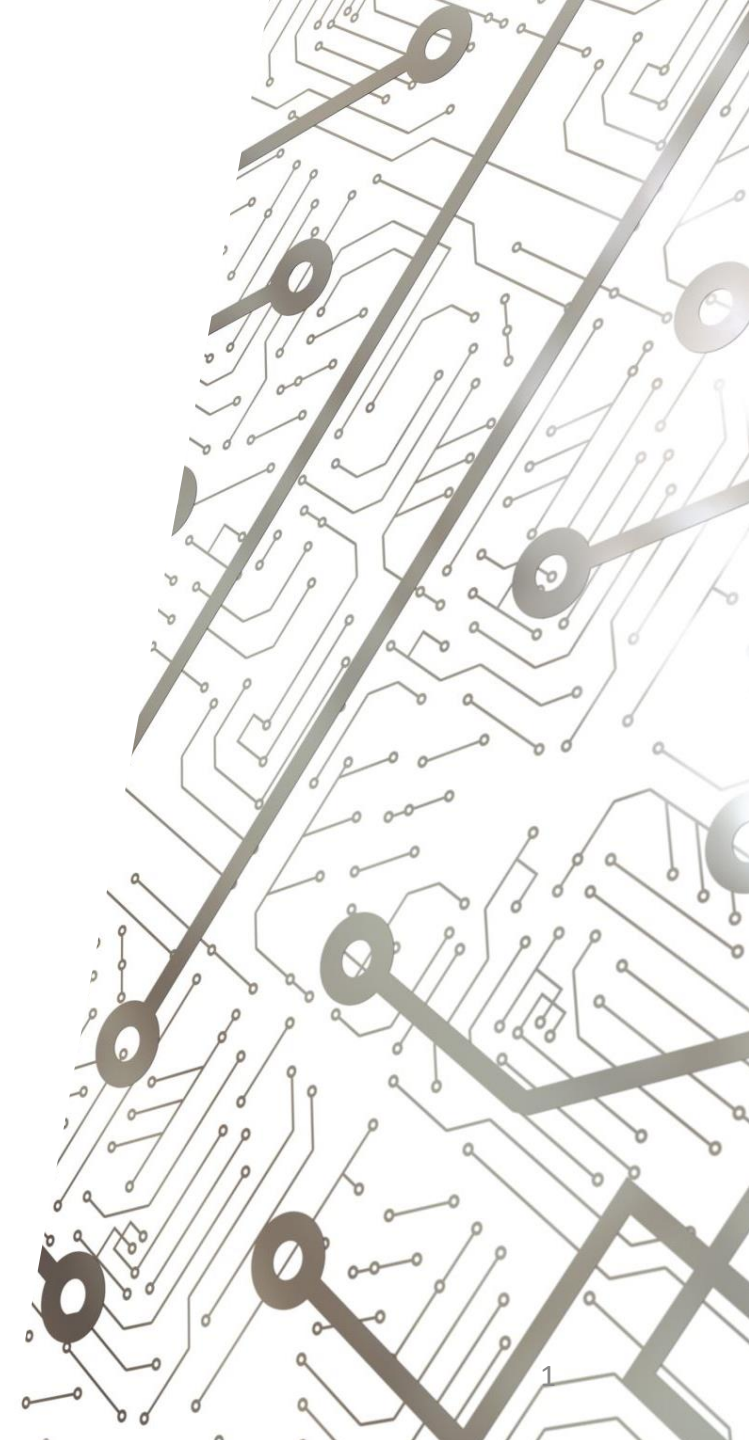
 ROS

The ROS logo consists of a 3x3 grid of dark blue dots to the left of the letters "ROS" in a large, dark blue, sans-serif font.

Nodes in Python 

The Python logo is a stylized, interlocking "P" and "Y" in blue and yellow.

Jacques Cloete



Contents

In this lecture, we shall cover:

- Creating and running Python code in Ubuntu
- Creating ROS nodes with Python
- Creating our first ROS application

Before We Begin

- Again, I strongly suggest bookmarking the following link:
<https://github.com/OxRAMSociety/RobotArm>

- All example code can be found in:

Tutorials/Software Tutorials (2022)/Example Scripts

Of course, code for this lecture will be in the Lecture 3 folder, and so on for future lectures

- I will provide code in these presentations, but refer to the Example Scripts to check your own!

Time to Create Our First Program!

- In the last lesson we created our own workspace, tutorial_ws, and created a package, tutorial_scripts, inside that workspace
- Time to create our first program; we will create a simple publisher-subscriber pair in Python
- **Create a `scripts` folder inside our `tutorial_scripts` package**
We will keep all our Python scripts in here
- **Create a new Python script inside it using Terminal:**
`touch Example_Publisher.py`

Creating Our First Publisher

- **Once the file has been created, double-click on it to open up the editor** (I actually prefer this approach to writing the code in Terminal – nicer interface!)
- **Add the following code to the top of the file:**

```
#!/usr/bin/env python3
```

```
import rospy      # Imports rospy, which provides all the basic ROS-based Python tools we need
import std_msgs.msg  # Imports the standard ROS message types
```

- The first line establishes the file as **Python 3** code, the two next ones import important **ROS-based Python tools**

Creating Our First Publisher

- Now let's define a **publisher**:

```
# Define a publisher to a new topic 'Example_Topic', which can take Strings as messages:  
pub = rospy.Publisher('Example_Topic', std_msgs.msg.String, queue_size=10)
```

```
# Note: queue_size determines the max. number of messages that can wait in the 'queue' to be published before any  
further additions are discarded (until space is made in the queue)
```

- Next thing to do is set up the code as a **ROS node**:

```
# Set up a new ROS node to act as the publisher:  
rospy.init_node('Example_Publisher')
```

- Then define the **rate** at which it will publish **messages**:

```
# Define the rate at which the publisher publishes messages:  
r = rospy.Rate(1)          # 1 Hz
```

Creating Our First Publisher

- Finally, let's add the **loop** that will run while the node is active
- The loop will get the node to publish a new message every second:

```
while not rospy.is_shutdown():    # While this node has not been terminated:

    # Publish the message "Example_Message" to Example_Topic
    pub.publish(std_msgs.msg.String("Example_Message"))

    # Sleep for an amount of time determined by the publishing frequency (1 second here)
    r.sleep()
```

Creating Our First Publisher

- The full Python script:

```
#!/usr/bin/env python3
```

```
import rospy      # Imports rospy, which provides all the basic ROS-based Python tools we need
import std_msgs.msg  # Imports the standard ROS message types
```

```
# Define a publisher to a new topic 'Example_Topic', which can take Strings as messages:
pub = rospy.Publisher('Example_Topic', std_msgs.msg.String, queue_size=10)
```

```
# Note: queue_size determines the max. number of messages that can wait in the 'queue' to be published before any
further additions are discarded (until space is made in the queue)
```

```
# Set up a new ROS node to act as the publisher:
rospy.init_node('Example_Publisher')
```

```
# Define the rate at which the publisher publishes messages:
r = rospy.Rate(1)      # 1 Hz
```

```
while not rospy.is_shutdown():  # While this node has not been terminated:
```

```
    # Publish the message "Example_Message" to Example_Topic
    pub.publish(std_msgs.msg.String("Example_Message"))
```

```
    # Sleep for an amount of time determined by the publishing frequency (1 second here)
    r.sleep()
```


Creating Our First Subscriber

- Now that we've created our first publisher, we need to make a subscriber to go with it!
- **Create another Python script using Terminal:**
touch Example_Publisher.py
- Again, add the necessary imports to the top of the script:

```
#!/usr/bin/env python3
```

```
import rospy      # Imports rospy, which provides all the basic ROS-based Python tools we need
import std_msgs.msg  # Imports the standard ROS message types
```

Creating Our First Subscriber

- When the subscriber receives a message, it calls a function to handle the message received – this is the **callback** function
- Let's create a callback function to print the message received in Terminal:

```
# Define function 'callback' that is called when the subscriber receives a message:  
def callback(message):
```

```
    # For this simple case, just print the message received in Terminal  
    rospy.loginfo("Message Received: %s",message.data)
```

Creating Our First Subscriber

- Finally, add the **main** code (this is acts as the point of execution for the program)
- It sets up the code as a **ROS node**, then more specifically a **subscriber**, then gets it to keep running until you shut it down

```
if __name__ == '__main__':      # Write your main code in here!

    # Set up a new ROS node to act as the subscriber:
    rospy.init_node('Example_Subscriber')

    # Define the node to act as a subscriber to 'Example_Topic', calling 'callback' when a message is received:
    rospy.Subscriber('Example_Topic', std_msgs.msg.String, callback)

    rospy.spin()      # Simply prevents Python from exiting until this node is terminated
```

Creating Our First Subscriber

- The full Python script:

```
#!/usr/bin/env python3
```

```
import rospy      # Imports rospy, which provides all the basic ROS-based Python tools we need
import std_msgs.msg  # Imports the standard ROS message types
```

```
# Define function 'callback' that is called when the subscriber receives a message:
```

```
def callback(message):
```

```
    # For this simple case, just print the message received in Terminal
    rospy.loginfo("Message Received: %s",message.data)
```

```
if __name__ == '__main__':      # Write your main code in here!
```

```
    # Set up a new ROS node to act as the subscriber:
    rospy.init_node('Example_Subscriber')
```

```
    # Define the node to act as a subscriber to 'Example_Topic', calling 'callback' when a message is received:
    rospy.Subscriber('Example_Topic', std_msgs.msg.String, callback)
```

```
    rospy.spin()      # Simply prevents Python from exiting until this node is terminated
```

Testing Our Code

- Before we can run our code, we need to give **permissions** to make it executable
- **In Terminal, run the following to give permissions:**
`sudo chmod a+x Example_Publisher.py Example_Subscriber.py`
- Note: You must do this for **every** new script you make!
- **Now, in three separate Terminals, run the following:**
 1. **`roscore`**
 2. **`roslaunch tutorial_scripts Example_Publisher.py`**
 3. **`roslaunch tutorial_scripts Example_Subscriber.py`**

In general, `roslaunch <package> <file>` to run a ROS program

Testing Our Code

- You should see something like this for Example_Subscriber:

```
jacques@JC-Workstation:~$ rosrun tutorial_scripts Example_Subscriber.py
[INFO] [1652564980.451556]: Message Received: Example_Message
[INFO] [1652564981.451324]: Message Received: Example_Message
[INFO] [1652564982.451504]: Message Received: Example_Message
[INFO] [1652564983.451813]: Message Received: Example_Message
[INFO] [1652564984.451400]: Message Received: Example_Message
[INFO] [1652564985.451348]: Message Received: Example_Message
[INFO] [1652564986.451307]: Message Received: Example_Message
[INFO] [1652564987.451324]: Message Received: Example_Message
[INFO] [1652564988.451280]: Message Received: Example_Message
[INFO] [1652564989.451654]: Message Received: Example_Message
[INFO] [1652564990.451457]: Message Received: Example_Message
[INFO] [1652564991.451319]: Message Received: Example_Message
[INFO] [1652564992.451706]: Message Received: Example_Message
[INFO] [1652564993.451602]: Message Received: Example_Message
[INFO] [1652564994.451615]: Message Received: Example_Message
```

Testing Our Code

- If you also run `rostopic list`, you will see `\Example_Topic` there
- Running `rostopic echo \Example_Topic` in a 4th Terminal:

```
^Cjacques@JC-Workstation:~$ rostopic echo \Example_Topic
data: "Example_Message"
---
data: "Example_Message"
---
data: "Example_Message"
---
data: "Example_Message"
---
data: "Example_Message"
---
data: "Example_Message"
---
data: "Example_Message"
---
```

Publishers and Subscribers in Action

- The publisher node 'Example_Publisher' is repeatedly publishing message 'Example_Message' onto the topic 'Example_Topic'
- The subscriber node 'Example_Subscriber' listens into the topic and receives the messages, printing them in Terminal

Application: Square Number Factory

- Time to put all our knowledge to use with an application!
- Consider a system where a **customer** generates a stream of numbers, requesting for a service to **square** them
- The numbers are squared by a separate **factory**
- A third member, the **receiver**, collects the square numbers from the factory and prints them out

Application: Square Number Factory

- I will provide less guidance for the basics now; all the tools you need can be found in previous lecture slides
- **Create three new Python scripts (again, in the **scripts** folder):**
 1. **Square_Number_Customer.py**
 2. **Square_Number_Factory.py**
 3. **Square_Number_Receiver.py**

Square Number Customer

- This node is just acting as a publisher
- Note: It publishes random integers between 1 and 10!

```
#!/usr/bin/env python3

import rospy
import std_msgs.msg
import random    # Used for random number generation

pub = rospy.Publisher('Square_Number_Order', std_msgs.msg.Int16, queue_size=10)

rospy.init_node('Square_Number_Customer')

r = rospy.Rate(2)    # 2 Hz

while not rospy.is_shutdown():

    order = random.randint(1,10)    # Randomly generate a new order

    rospy.loginfo("Number to be Squared: %d",order)

    pub.publish(std_msgs.msg.Int16(order))    # Publish order

    r.sleep()
```

Square Number Factory

- This node is acting as a publisher AND subscriber
- Note: It publishes its messages from **INSIDE** its callback!
Whenever it receives a message, it publishes one in response

```
#!/usr/bin/env python3

import rospy
import std_msgs.msg

pub = rospy.Publisher('Square_Number_Processed', std_msgs.msg.Int16, queue_size=10)

def callback(message):

    rospy.loginfo("Order Received: %d",message.data)

    processed_order = message.data*message.data      # Process order (i.e. square it)

    rospy.loginfo("Processed Order: %d",processed_order)

    pub.publish(std_msgs.msg.Int16(processed_order)) # Publish processed order

if __name__ == '__main__':

    rospy.init_node('Square_Number_Factory')

    rospy.Subscriber('Square_Number_Order', std_msgs.msg.Int16, callback)    # Listen for orders

    rospy.spin()
```

Square Number Receiver

- This node is just acting as a subscriber

```
#!/usr/bin/env python3

import rospy
import std_msgs.msg

def callback(message):

    rospy.loginfo("Square Number Received: %d",message.data) # Display received square number

if __name__ == '__main__':

    rospy.init_node('Square_Number_Receiver')

    rospy.Subscriber('Square_Number_Processed', std_msgs.msg.Int16, callback) # Listen for processed orders

    rospy.spin()
```

Testing Our Program

- Try running the nodes! As always, remember **roscore** and to first give **permissions** to each new script!
- You should see something like this:

```
[1652567104.509452]: Number to be Squared: 4  
[1652567105.009445]: Number to be Squared: 6  
[1652567105.509617]: Number to be Squared: 8  
[1652567106.009449]: Number to be Squared: 2  
[1652567106.509397]: Number to be Squared: 5  
[1652567107.009592]: Number to be Squared: 6  
[1652567107.509456]: Number to be Squared: 7  
[1652567108.009485]: Number to be Squared: 8  
[1652567108.509408]: Number to be Squared: 6  
[1652567109.009387]: Number to be Squared: 6  
[1652567109.509302]: Number to be Squared: 6  
[1652567110.009583]: Number to be Squared: 10  
[1652567110.509373]: Number to be Squared: 3  
[1652567111.009404]: Number to be Squared: 2  
[1652567111.509265]: Number to be Squared: 3  
[1652567112.009409]: Number to be Squared: 10  
[1652567112.509387]: Number to be Squared: 3  
[1652567113.009526]: Number to be Squared: 2  
[1652567113.509718]: Number to be Squared: 10  
[1652567114.009459]: Number to be Squared: 7
```

Customer

```
[1652567164.018283]: Processed Order: 9  
[1652567164.513888]: Order Received: 2  
[1652567164.517609]: Processed Order: 4  
[1652567165.015033]: Order Received: 9  
[1652567165.018699]: Processed Order: 81  
[1652567165.514714]: Order Received: 5  
[1652567165.519235]: Processed Order: 25  
[1652567166.014596]: Order Received: 10  
[1652567166.018242]: Processed Order: 100  
[1652567166.520172]: Order Received: 7  
[1652567166.523923]: Processed Order: 49  
[1652567167.014444]: Order Received: 3  
[1652567167.018492]: Processed Order: 9  
[1652567167.513529]: Order Received: 4  
[1652567167.515694]: Processed Order: 16  
[1652567168.013505]: Order Received: 2  
[1652567168.016269]: Processed Order: 4  
[1652567168.513361]: Order Received: 6
```

Factory

```
[1652567167.021391]: Square Number Received: 9  
[1652567167.519212]: Square Number Received: 16  
[1652567168.020201]: Square Number Received: 4  
[1652567168.521908]: Square Number Received: 36  
[1652567169.016939]: Square Number Received: 100  
[1652567169.518016]: Square Number Received: 1  
[1652567170.019966]: Square Number Received: 81  
[1652567170.520799]: Square Number Received: 64  
[1652567171.019966]: Square Number Received: 100  
[1652567171.520092]: Square Number Received: 81  
[1652567172.020525]: Square Number Received: 81  
[1652567172.520951]: Square Number Received: 16  
[1652567173.021216]: Square Number Received: 49  
[1652567173.519859]: Square Number Received: 25  
[1652567174.019742]: Square Number Received: 25  
[1652567174.523136]: Square Number Received: 64  
[1652567175.023552]: Square Number Received: 9  
[1652567175.521141]: Square Number Received: 36
```

Receiver

Closing Thoughts

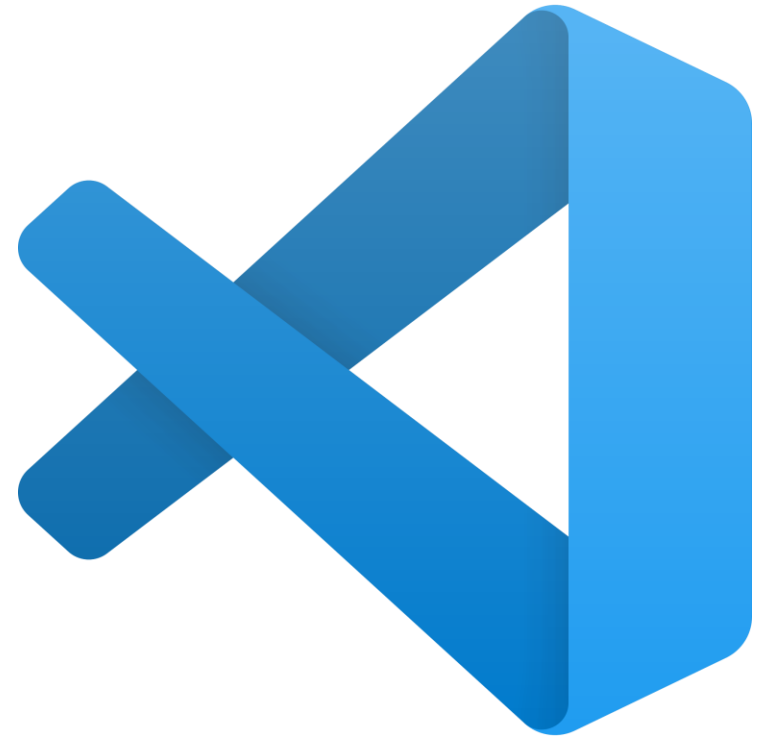
- Note that our new program uses 3 nodes and 2 topics
- You may be wondering; why couldn't the customer and receiver be the same node?
- Well, as great as simple **publisher/subscriber** systems are, they have their limits
- To repeatedly publish messages with a time-delay between means that we can't be continually listening for new messages at the same time; this is simply how the while-loop works, unfortunately!

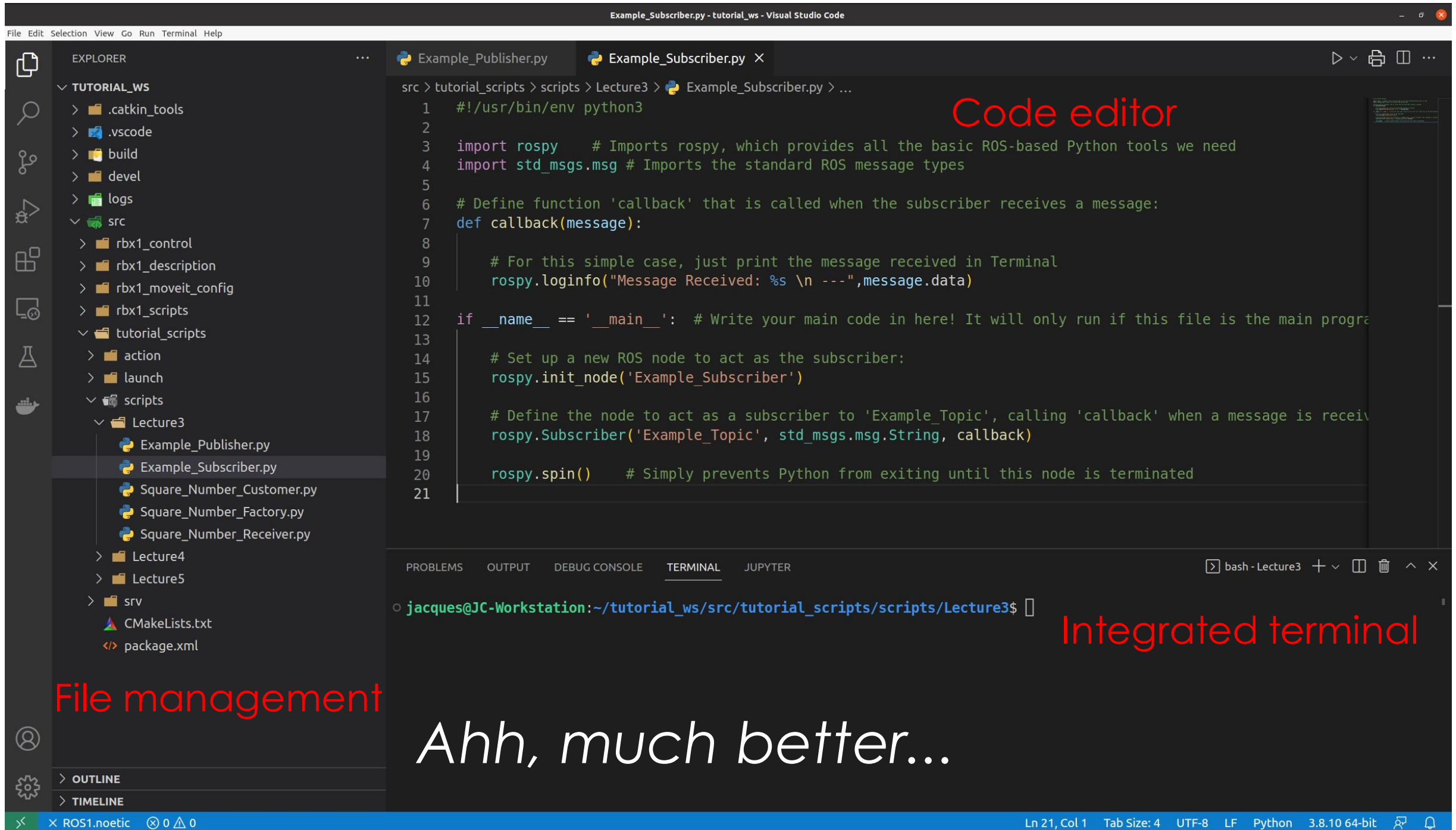
A Better Solution?

- Thankfully, ROS has us covered with **ROS services**
- These allow you to set up a client and a server; the **client** sends out requests which a **server** uses to complete a task
- Once it's done, the server sends the output back to the client
- This way, the 'customer' will also be the 'receiver' of the output once the task is complete
- More on this next time!

One Last Thing – Visual Studio Code

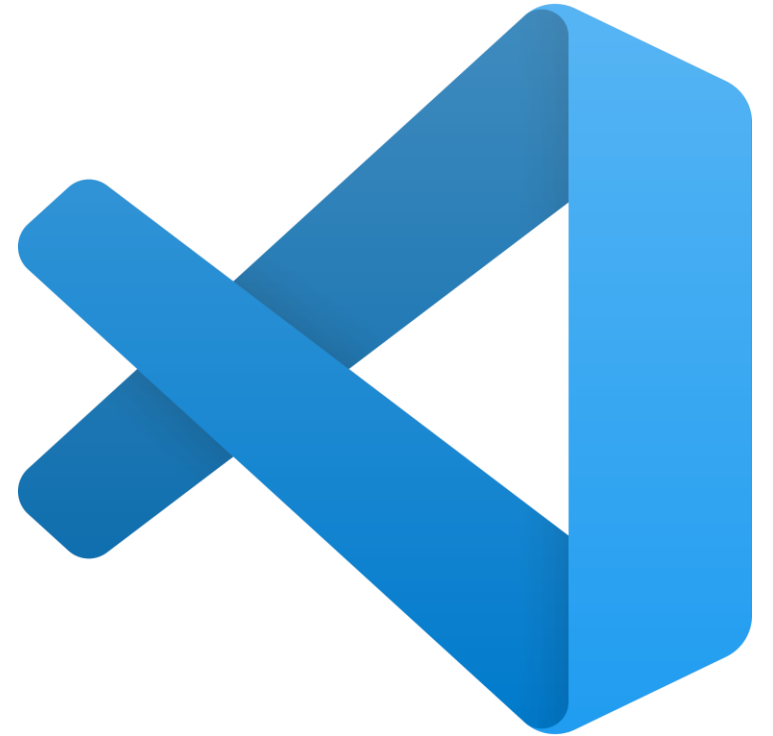
- While the standard text editor has been sufficient for creating these simple programs, a proper **code editor** is all but necessary for larger projects
- I suggest installing **VS Code**; it provides:
 - Real-time error checking (and quick fixes!)
 - Debugging
 - An integrated Terminal
 - Easy file and folder management
 - ...and much more!





Visual Studio Code – Extensions

- Many **extensions** exist for VS Code, and will provide even more functionality
- I suggest installing these extensions:
 - Python
 - Pylance
 - vscode-icons
 - ROS
- There are also some great extensions for C++ (if you're familiar with the language)



Summary

We covered:

- Creating and running Python code in Ubuntu
- Creating ROS nodes with Python
- Creating our first ROS application

Homework: Go over the code and make sure you can follow what's going on, (optional) install VS Code

Next time, we will learn about ROS Services!



Thank You!

Any Questions? Contact jacques.cloete@trinity.ox.ac.uk