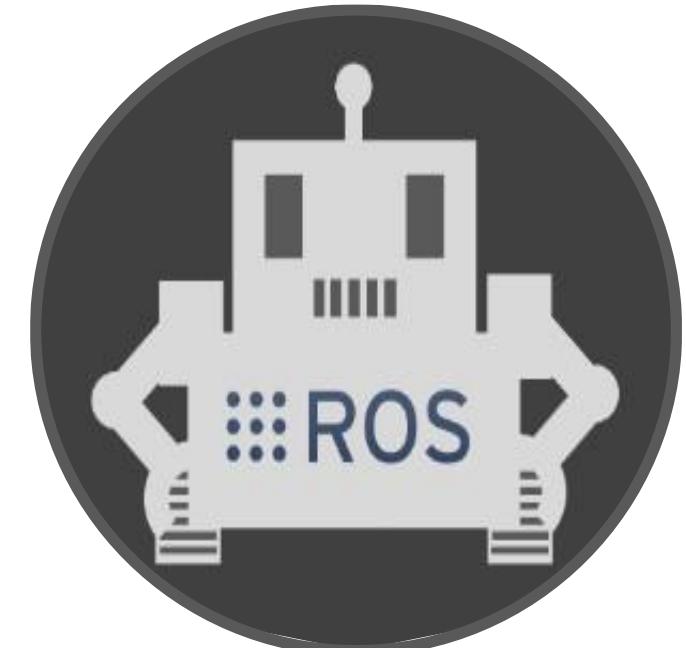


# ROS 기초 강의

## Chapter 11. 실력 상승 노하우

구선생 로보틱스



# 강의 자료 다운로드

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ROS 기초 강의 강의노트

[https://drive.google.com/drive/folders/1rRwS2j98HNyj5ls\\_yUXEGj3OILvMPtrz?usp=drive\\_link](https://drive.google.com/drive/folders/1rRwS2j98HNyj5ls_yUXEGj3OILvMPtrz?usp=drive_link)

# ROS 실력 상승 노하우

## ROS Wiki 활용

Google nanoscan ros

전체 이미지 동영상 쇼핑 뉴스 더보기 도구

검색결과 약 3,070개 (0.31초)

도움말: 한국어 검색결과만 검색합니다. 환경설정에서 검색 언어를 지정할 수 있습니다.

[http://wiki.ros.org/sick\\_safetyscanners](http://wiki.ros.org/sick_safetyscanners)

sick\_safetyscanners - ROS Wiki

2019. 12. 12. — A ROS Driver which reads the raw data from the SICK Safety Scanner and publishes the data as a laser\_scan msg. · Supported are all microScan3, ...

[Installation](#) · [Starting](#)



동영상 강의 - 마무리  
[https://youtu.be/3k7oYeeaRhl?si=sq6\\_lyoWkkxjnszF](https://youtu.be/3k7oYeeaRhl?si=sq6_lyoWkkxjnszF)

**sick\_safetyscanners**

melodic noetic Show EOL distros:

Documentation Status

## Package Summary

✓ Released ✓ Continuous Integration ✓ Documented

Provides an Interface to read the sensor output of a SICK Safety Scanner

- Maintainer status: developed
- Maintainer: Lennart Puck <puck AT fzi DOT de>
- Author: Lennart Puck
- License: ALv2
- Source: git [https://github.com/SICKAG/sick\\_safetyscanners.git](https://github.com/SICKAG/sick_safetyscanners.git) (branch: master)

**Package Links**

[Code API](#) [Msg/Srv API](#) [FAQ](#) [Changelog](#) [Change List](#) [Reviews](#)

**Dependencies (8)** [Jenkins Jobs \(10\)](#)

로봇 관련 패키지가 필요할 경우 해당 검색어 + ros 를 검색하면  
 대부분 ros wiki 문서가 있다.

# ROS 실력 상승 노하우

## Readme 문서 정독

### Getting started

The ROS driver will be released as a debian package, and therefore can be installed from binaries or from source.

### Prerequisites

- Linux
- Working ROS-Distro
- Correctly setup SICK Safety Scanner
- Connected SICK Safety Scanner and a correctly setup ethernet network. Both the host and the sensor have to be in the same network.

### Installation

In the following instructions, replace `<rosdistro>` with the name of your ROS distro (e.g., `kinetic`).

처음보는 패키지 사용시 Readme 문서를 따르는 것이 베스트이다

# ROS 실력 상승 노하우

## Document 검색

Google sensor data/laserscan document

전체 이미지 동영상 뉴스 쇼핑 더보기

검색결과 약 209,000개 (0.40초)

[http://docs.ros.org > api > sensor\\_msgs > html > msg](http://docs.ros.org/api/sensor_msgs/html/msg/sensor_msgs/_LaserScan.html)

[sensor\\_msgs/LaserScan Message - ROS Documentation](http://docs.ros.org/api/sensor_msgs/html/msg/sensor_msgs/_LaserScan.html)

sensor\_msgs/LaserScan Message. File: `sensor_msgs/LaserScan.msg`. Raw Message Definition.

```
# Single scan from a planar laser range-finder
# If you have another ranging device with different behavior (e.g. a sonar
# array), please find or create a different message, since applications
# will make fairly laser-specific assumptions about this data
Header header          # timestamp in the header is the acquisition time of
                        # the first ray in the scan.
                        #
                        # in frame frame id, angles are measured around
                        # the positive Z axis (counterclockwise, if Z is up)
                        # with zero angle being forward along the x axis
float32 angle_min      # start angle of the scan [rad]
float32 angle_max      # end angle of the scan [rad]
float32 angle_increment # angular distance between measurements [rad]
float32 time_increment  # time between measurements [seconds] - if your scanner
                        # is moving, this will be used in interpolating position
                        # of 3d points
float32 scan_time       # time between scans [seconds]
float32 range_min       # minimum range value [m]
float32 range_max       # maximum range value [m]
float32[] ranges        # range data [m] (Note: values < range_min or > range_max should be discarded)
float32[] intensities   # intensity data [device-specific units]. If your
                        # device does not provide intensities, please leave
                        # the array empty.
```

ROS 내부의 자료형 및 소스코드를 알고 싶을 시  
해당 키워드 + document라고 검색 시 자료가 나온다

# ROS 실력 상승 노하우

## ROS info 명령어 활용

### 1) Ros topic 정보

```
$ rostopic info <토픽_이름>
```

### 2) Ros node 정보

```
$ rosnode info <노드_이름>
```

### 3) Ros service 정보

```
$ rosnode service <서비스_이름>
```

Info 명령어를 이용하면 패키지를 쉽게 분석할 수 있다.

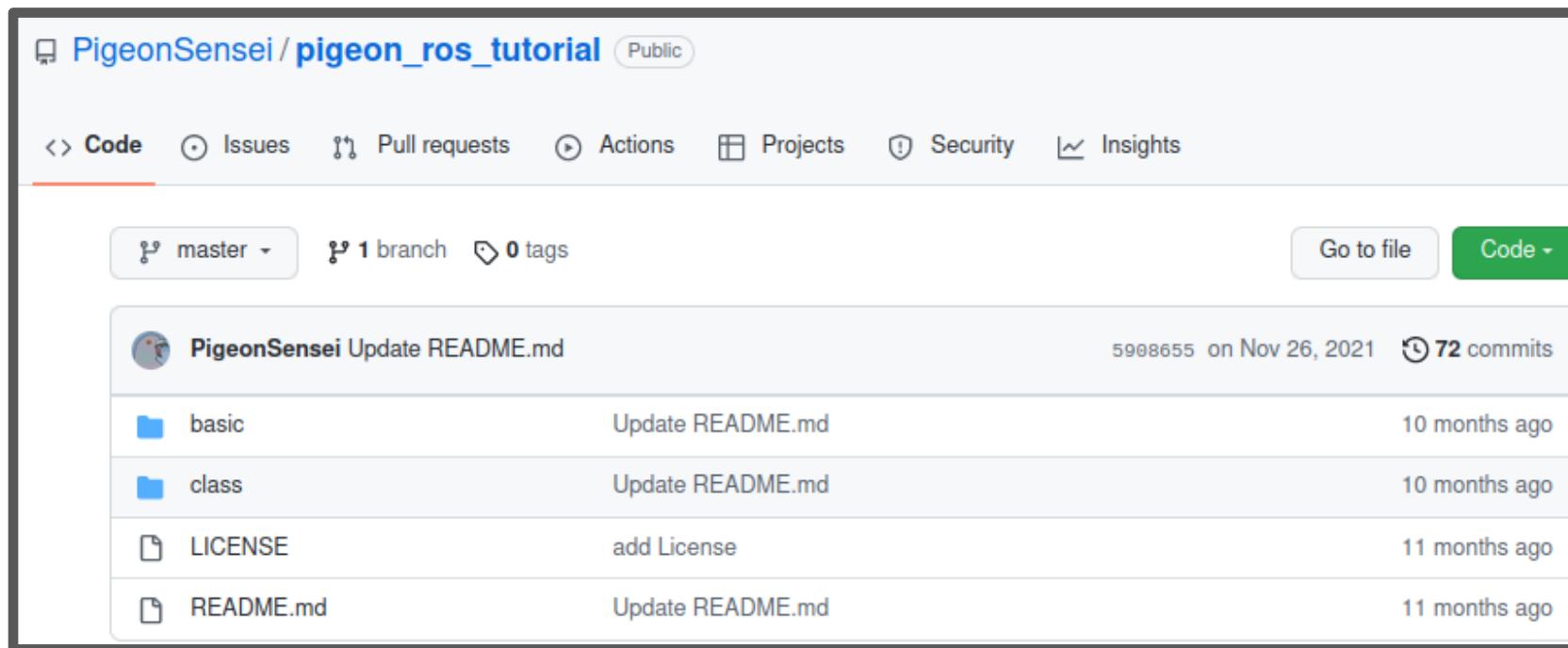
# ROS 실력 상승 노하우

## ROS info 명령어 활용



ROS 레퍼런스 소스코드

[https://github.com/PigeonSensei/pigeon\\_ros\\_tutorial](https://github.com/PigeonSensei/pigeon_ros_tutorial)



PigeonSensei / **pigeon\_ros\_tutorial** Public

<> **Code** Issues Pull requests Actions Projects Security Insights

master 1 branch 0 tags Go to file Code ▾

Author	Commit Message	Date	Commits
PigeonSensei	Update README.md	5908655 on Nov 26, 2021	72
	basic	Update README.md	10 months ago
	class	Update README.md	10 months ago
	LICENSE	add License	11 months ago
	README.md	Update README.md	11 months ago

ROS 소스코드 레퍼런스를 활용하면 쉽게 프로그래밍 가능하다.

# 감사합니다

구선생 로보틱스

