2022

INFO 802

Master Advanced Mechatronics

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POLYTECH ANNECY-CHAMBÉRY

ROS

ROS Command Tools Tutorial 1

Objectives

At the end of this lecture, you are excepted to :

- Use ROS command line tools to get information on nodes, topics and message type
- Know what a ROS message is made up of.
- Find which library a ROS message comes from.

ROS Command Tools

Turtlesim

Turtle_teleop_key node

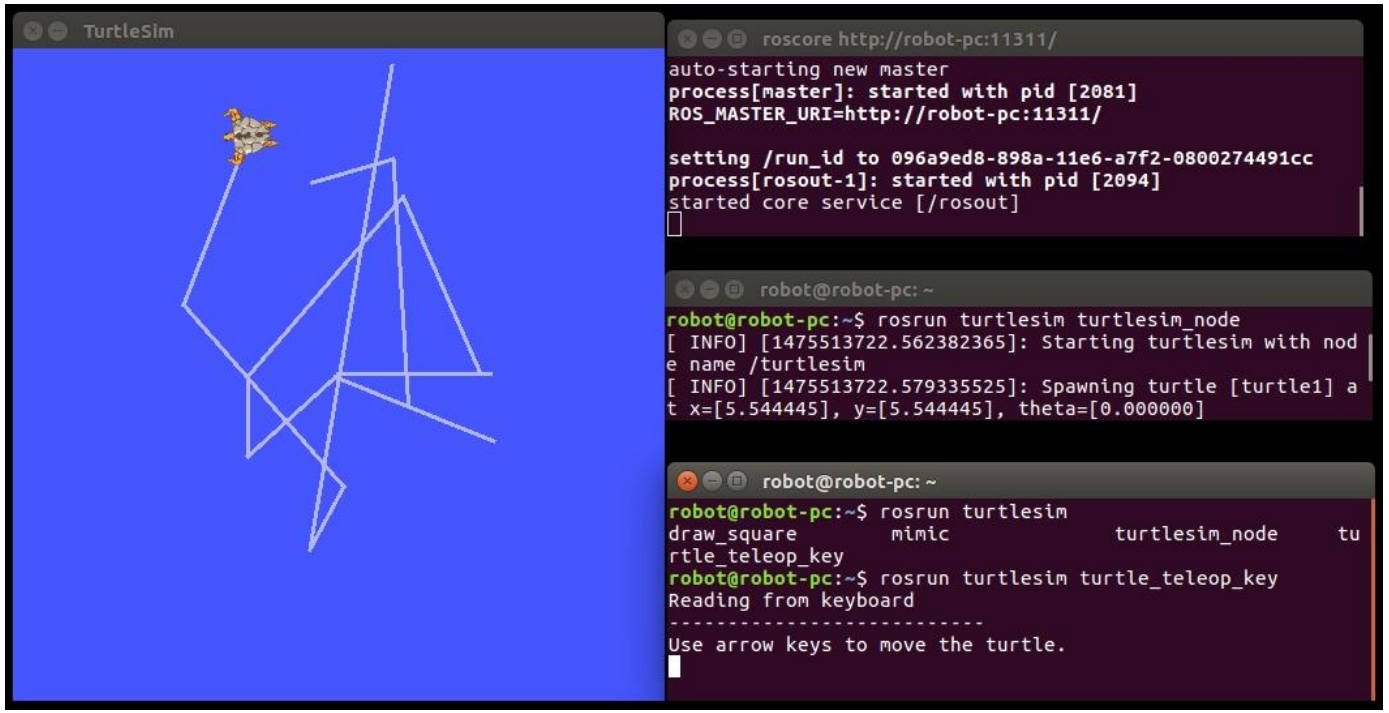
Test moving the turtle
(with the *turtle_teleop_key* node)

Recall: Open a terminal for each command

```
> roscore
```

```
> rosrun turtlesim turtlesim_node
```

```
> rosrun turtlesim turtle_teleop_key
```



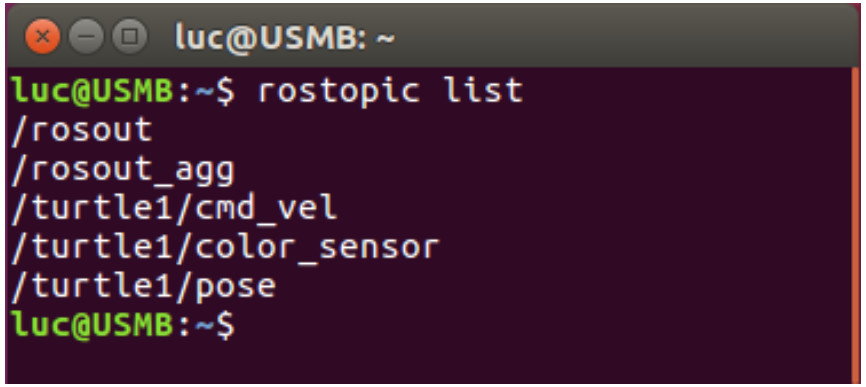
The terminal which *turtle_teleop_key* is running on MUST be selected.
Change the turtle's position by pressing arrow keys on the keyboard.

ROS Command Tools

topic

List all active topics on ROS:

```
> rostopic list
```



Display which message is used on a topic:

```
> rostopic type [topic_name]
```

```
luc@USMB:~$ rostopic type /turtle1/pose
turtlesim/Pose
```

Get more information on a topic:

```
> rostopic info [topic_name]
```

```
luc@USMB:~$ rostopic type /turtle1/pose
Type: turtlesim/Pose

Publishers:
 * /turtlesim (http://localhost:40351/)

Subscribers: None
```

ROS Command Tools

node

List all active node running on ROS:

```
> rosnode list
```

```
luc@USMB:~$ rosnode list
/rosout
/teleop_turtle
/turtlesim
```

Display information including publication/subscription:

```
> rosnode info [node_name]
```

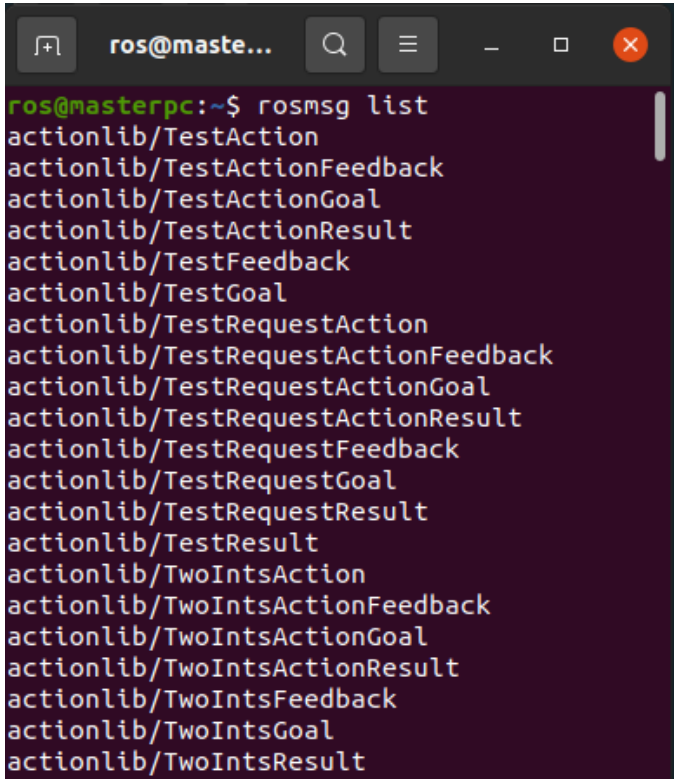
```
luc@USMB:~$ rosnode info turtlesim
--------------------------------------------------------------------------------
Node [/turtlesim]
Publications:
 * /rosout [rosgraph_msgs/Log]
 * /turtle1/color_sensor [turtlesim/Color]
 * /turtle1/pose [turtlesim/Pose]

Subscriptions:
 * /turtle1/cmd_vel [geometry_msgs/Twist]

Services:
 * /clear
 * /kill
 * /reset
 * /spawn
 * /turtle1/set_pen
 * /turtle1/teleport_absolute
```

ROS Command Tools

msg

Show all messages available in ROS:

```
> rosmsg list
```



Show the content of a message type:

```
> rosmsg show [message_type]
```

```
> rosmsg show turtlesim/Pose
```

```
luc@USMB:~$ rosmsg show turtlesim/Pose
[turtlesim/Pose]:
  float64 x
  float64 y
  float64 theta
  float64 linear_velocity
  float64 angular_velocity
```

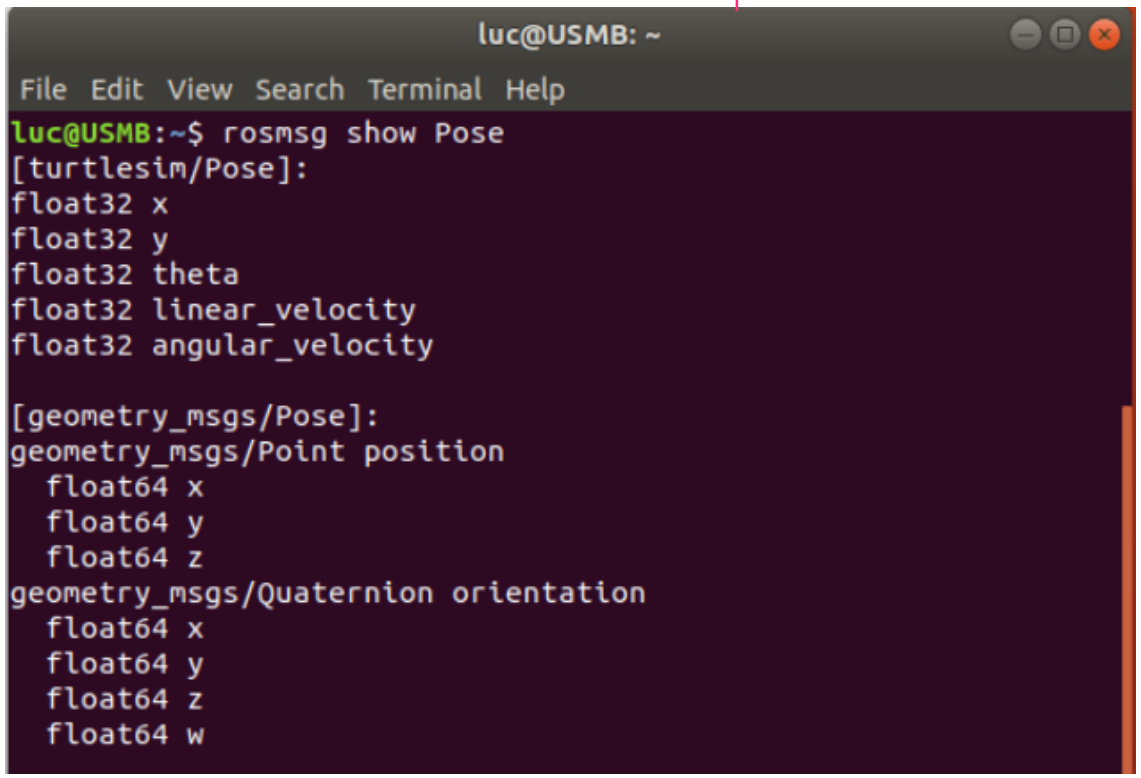
ROS Command Tools

msg

See message definition information:

```
> rosmsg show [message_type]
```

```
> rosmsg show Pose
```



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

ROS Command Tools

System File

Get information on packages

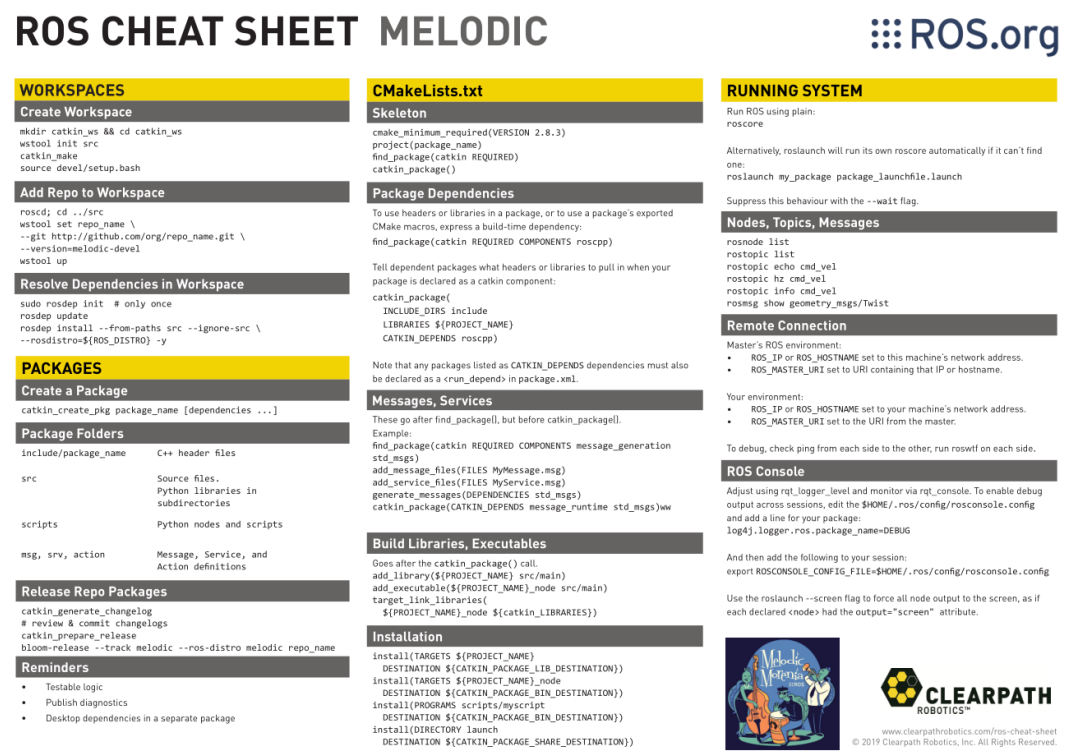
```
> rospack find [package_name]
```

Change directory (cd) directly to a package or a stack

```
> roscd [location_name[/subdir]]
```

ls directly in a package by name rather than by absolute path

```
> rosls [location_name[/subdir]]
```



ROS CHEAT SHEET MELODIC — ROS.org

WORKSPACES

Create Workspace

```
mkdir catkin_ws && cd catkin_ws
wstool init src
catkin_make
source devel/setup.bash
```

Add Repo to Workspace

```
roscd; cd ../src
wstool set repo_name \
--git http://github.com/org/repo_name.git \
--version=melodic-devel
wstool up
```

Resolve Dependencies in Workspace

```
sudo rosdep init  # only once
rosdep update
rosdep install --from-paths src --ignore-src \
--rosdistro=${ROS_DISTRO} -y
```

PACKAGES

Create a Package

```
catkin_create_pkg package_name [dependencies ...]
```

Package Folders

include/package_name	C++ header files
src	Source files. Python libraries in subdirectories
scripts	Python nodes and scripts
msg, srv, action	Message, Service, and Action definitions

Release Repo Packages

```
catkin_generate_changelog
# review & commit changelogs
catkin_prepare_release
bloom-release --track melodic --ros-distro melodic repo_name
```

Reminders

- Testable logic
- Publish diagnostics
- Desktop dependencies in a separate package

CMakeLists.txt

Skeleton

```
cmake_minimum_required(VERSION 2.8.3)
project(package_name)
find_package(catkin REQUIRED)
catkin_package()
```

Package Dependencies

To use headers or libraries in a package, or to use a package's exported CMake macros, express a build-time dependency:

```
find_package(catkin REQUIRED COMPONENTS roscpp)
```

Tell dependent packages what headers or libraries to pull in when your package is declared as a catkin component:

```
catkin_package(
  INCLUDE_DIRS include
  LIBRARIES ${PROJECT_NAME}
  CATKIN_DEPENDS roscpp)
```

Note that any packages listed as CATKIN_DEPENDS dependencies must also be declared as a <run_depend> in package.xml.

Messages, Services

These go after find_package(), but before catkin_package().
Example:

```
find_package(catkin REQUIRED COMPONENTS message_generation
std_msgs)
add_message_files(FILES MyMessage.msg)
add_service_files(FILES MyService.msg)
generate_messages(DEPENDENCIES std_msgs)
catkin_package(CATKIN_DEPENDS message_runtime std_msgs)ww
```

Build Libraries, Executables

Goes after the catkin_package() call.

```
add_library(${PROJECT_NAME} src/main)
add_executable(${PROJECT_NAME}_node src/main)
target_link_libraries(
  ${PROJECT_NAME}_node ${catkin_LIBRARIES})
```

Installation

```
install(TARGETS ${PROJECT_NAME}
  DESTINATION ${CATKIN_PACKAGE_LIB_DESTINATION})
install(TARGETS ${PROJECT_NAME}_node
  DESTINATION ${CATKIN_PACKAGE_BIN_DESTINATION})
install(PROGRAMS scripts/myscript
  DESTINATION ${CATKIN_PACKAGE_BIN_DESTINATION})
install(DIRECTORY launch
  DESTINATION ${CATKIN_PACKAGE_SHARE_DESTINATION})
```

RUNNING SYSTEM

Run ROS using plain:

```
roscore
```

Alternatively, roslaunch will run its own roscore automatically if it can't find one:

```
roslaunch my_package package_launchfile.launch
```

Suppress this behaviour with the --wait flag.

Nodes, Topics, Messages

```
rosnode list
rostopic list
rostopic echo cmd_vel
rostopic hz cmd_vel
rostopic info cmd_vel
rosmsg show geometry_msgs/Twist
```

Remote Connection

Master's ROS environment:

- ROS_IP or ROS_HOSTNAME set to this machine's network address.
- ROS_MASTER_URI set to URI containing that IP or hostname.

Your environment:

- ROS_IP or ROS_HOSTNAME set to your machine's network address.
- ROS_MASTER_URI set to the URI from the master.

To debug, check ping from each side to the other, run roswtf on each side.

ROS Console

Adjust using rqt_logger_level and monitor via rqt_console. To enable debug output across sessions, edit the $HOME/.ros/config/rosconsole.config and add a line for your package:

```
log4j.logger.ros.package_name=DEBUG
```

And then add the following to your session:

```
export ROSCONSOLE_CONFIG_FILE=$HOME/.ros/config/rosconsole.config
```

Use the roslaunch --screen flag to force all node output to the screen, as if each declared <node> had the output="screen" attribute.

CLEARPATH ROBOTICS™

www.clearpathrobotics.com/ros-cheat-sheet

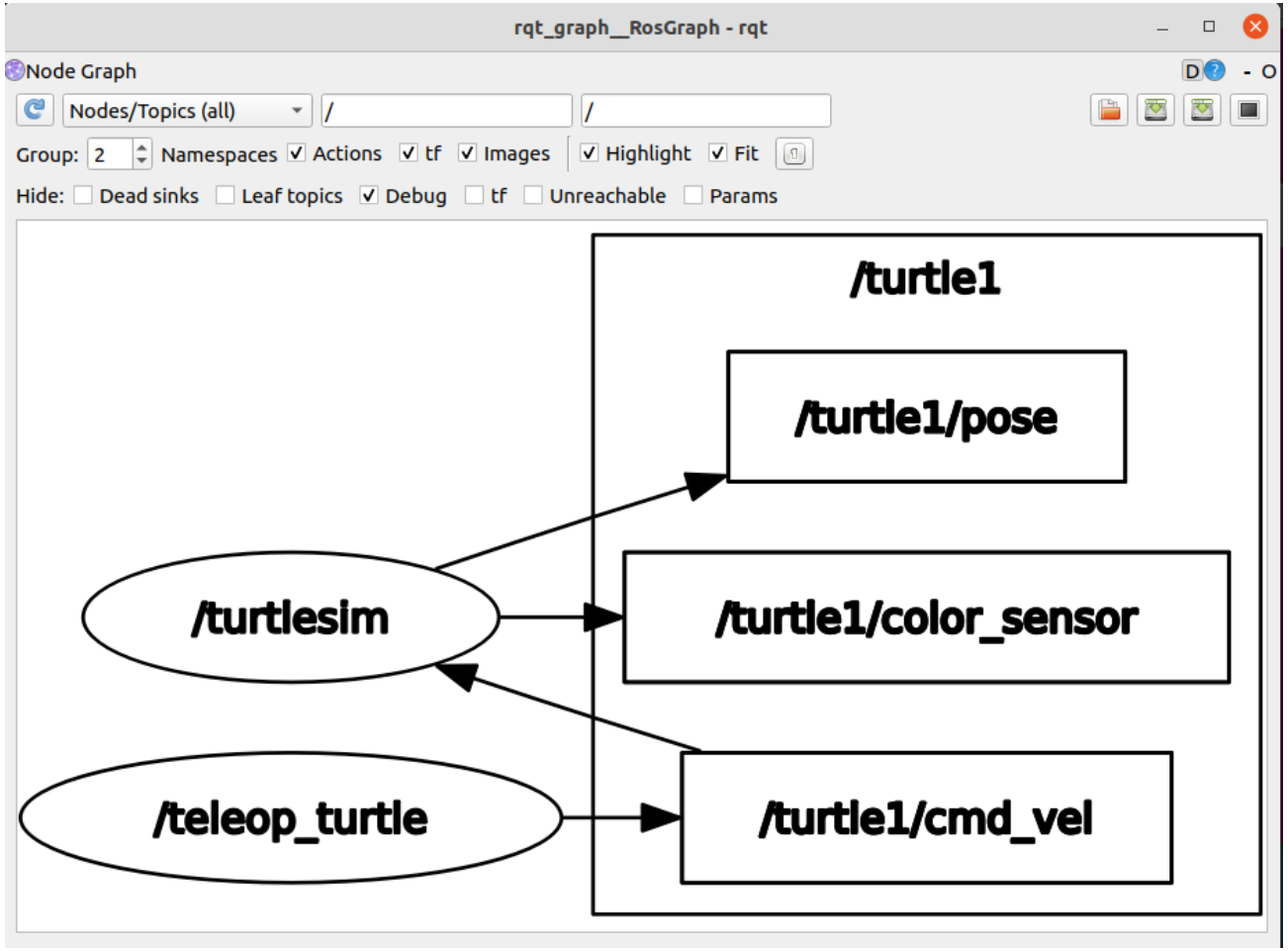
More info

http://wiki.ros.org/ROS/Tutorials/NavigatingTheFilesystem

ROS computation graph *rqt*

Visualize running topics and nodes

```
> rosrun rqt_graph rqt_graph
```

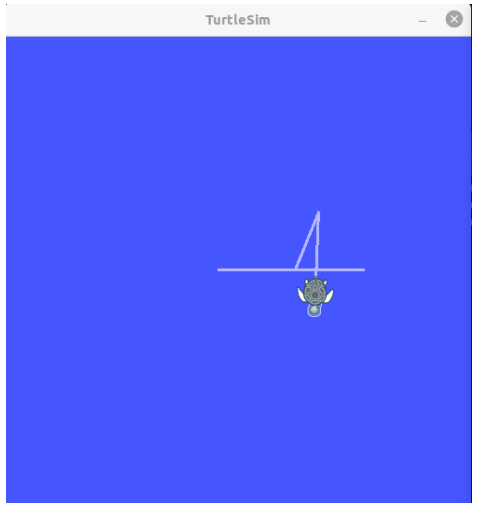


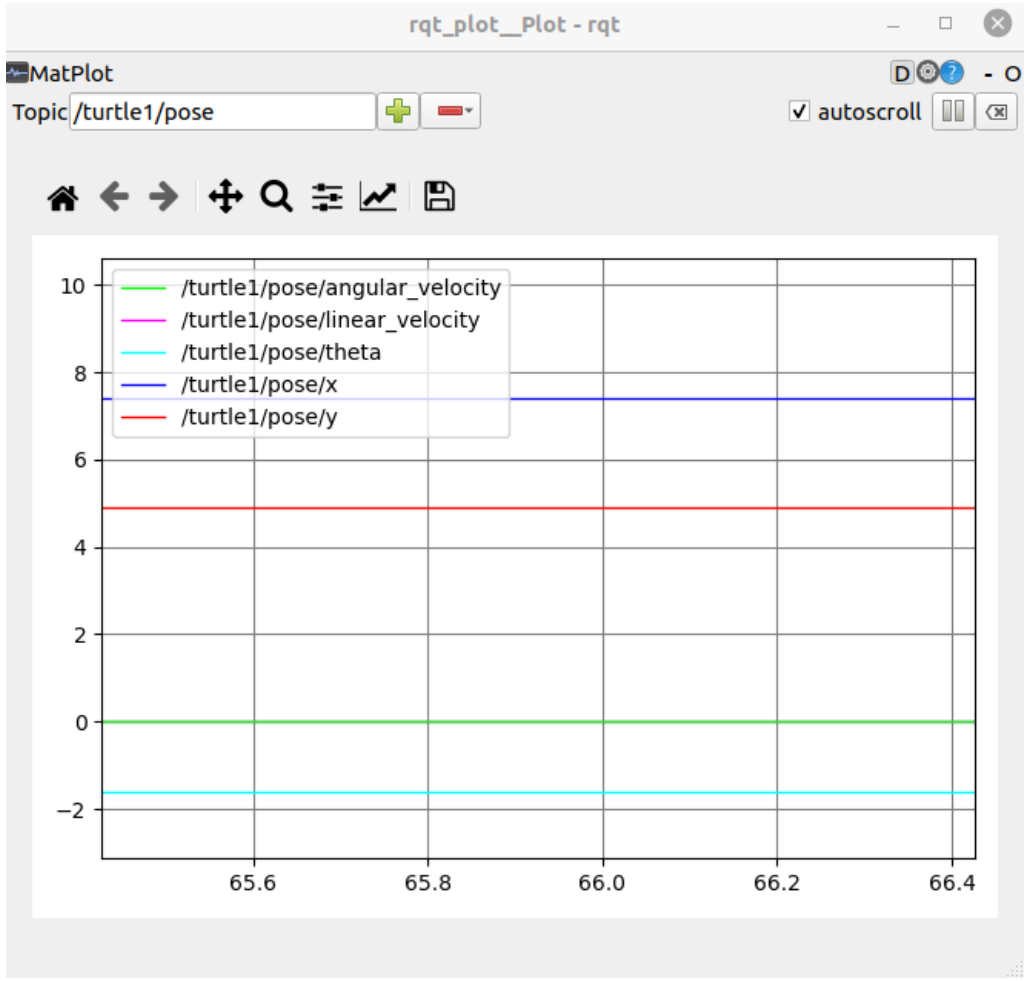
ROS computation graph *rqt*

Visualize running topics and nodes

```
> rosrun rqt_plot rqt_plot
```

It shows the values published on a topic

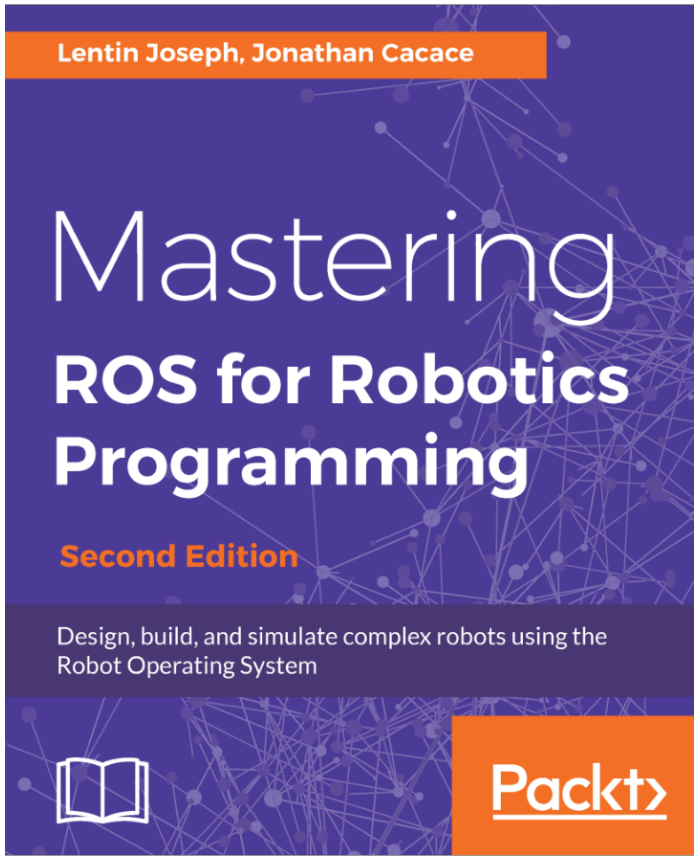


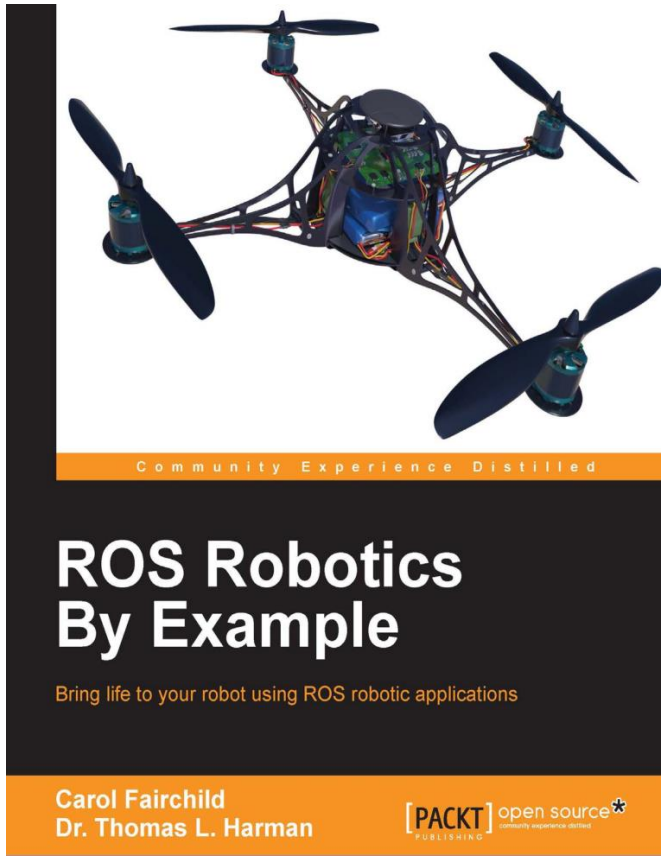


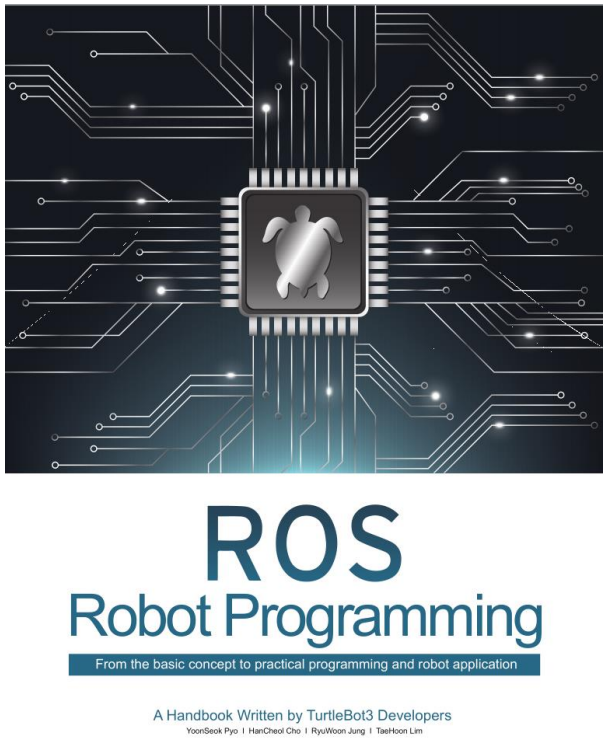
Further References

- 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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