Table of Contents

1. ROS Tutorials 2

Welcome

Project Willy

- History of Willy
- Project Willy
- Publicity
- Sponsors

Getting started

- Development Guide
- Driving Willy
- Documentation

Build of Willy

- Design history
- Requirements
- Design reference
- Physical build
- Hardware

Robotic Operating System

- Introduction to ROS
- ROS Tutorials
- Multi master

Architecture

- Software Architecture
- Hardware Architecture
- Skylab Architecture
- ROS topic design

Hardware nodes

- sensor node
- si node
- power node
- WillyWRT

Components

- ROS master
- New ROS master on Lubuntu
- Brain

- Sonar
- Lidar
- Localization and navigation
- Motor controller
- Joystick
- Social interaction
- Speech
- Speech recognition

Skylab

- Setup Skylab
- Python scripts
- Webserver
- Functions of the webserver
- Skylab servers
- ROS installation on Ubuntu VMs in Skylab
- DNS,DHCP, pfSense & Ubuntu

Radeffect App

- Radeffect App

Lessons learned

- Todo & Advice
- Lessons Learned

Archive

- Previous Groups
- Research Archive

1. ROS Tutorials

We found out the hard way, multiple times, that ROS can be quite difficult to comprehend. The principle seems rather easy, have a working network, communicate on TCP-IP and DNS name, and start coding. However, there are a variaty of pitfalls where you can go wrong.

We have used multiple ROS tutorials to understand more of the technical aspects of ROS as well as the (im)possibilities it holds. Due to these tutorials we kept Willy as it was, but also gained knowledge about ROS. Therefore we strongly suggest to read and try some of the tutorials ROS provides on their webpage.

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