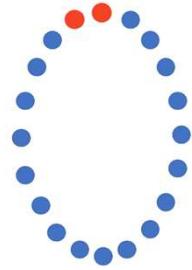




SEMTRON

ZERO

Robotics Development Framework, Workspace & Workflow



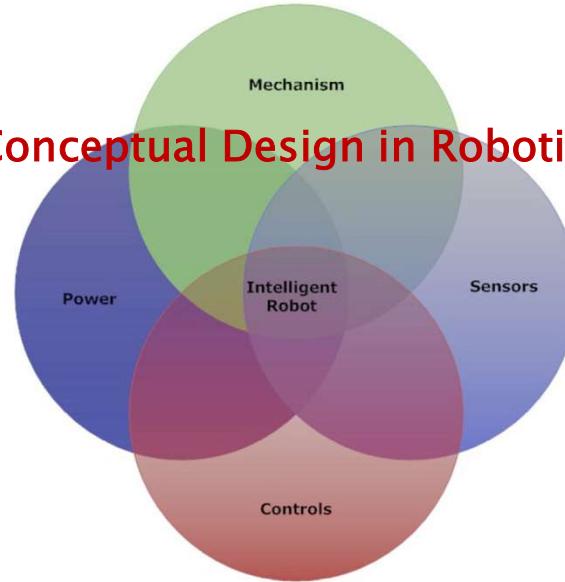
<https://tinyurl.com/5b5s9ham>

1



SEMTRON

Conceptual Design in Robotics



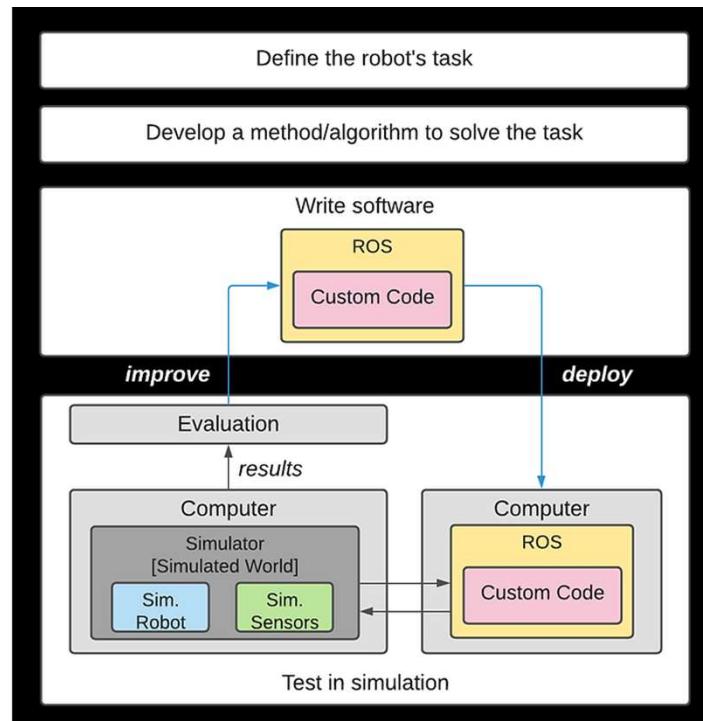
2



The requirements for a robot that collects table tennis balls:

- (a) It should be applicable to the setting of general table tennis courts, with a size of 8 m × 16 m;
- (b) It can collect at least 30 table tennis balls within a reasonable time as well as show the number of table tennis balls collected;
- (c) When no one is inside the table tennis court, it can be activated to start the process for collecting table tennis balls automatically within the designated area;
- (d) There should a basket to hold the collected table tennis balls and allow players to take out the balls easily to continue practising.

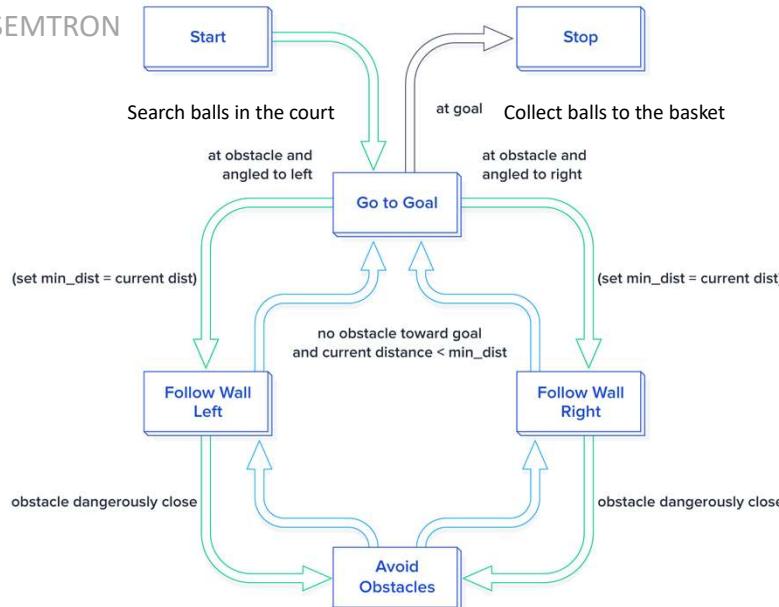
3



4



SEMTRON

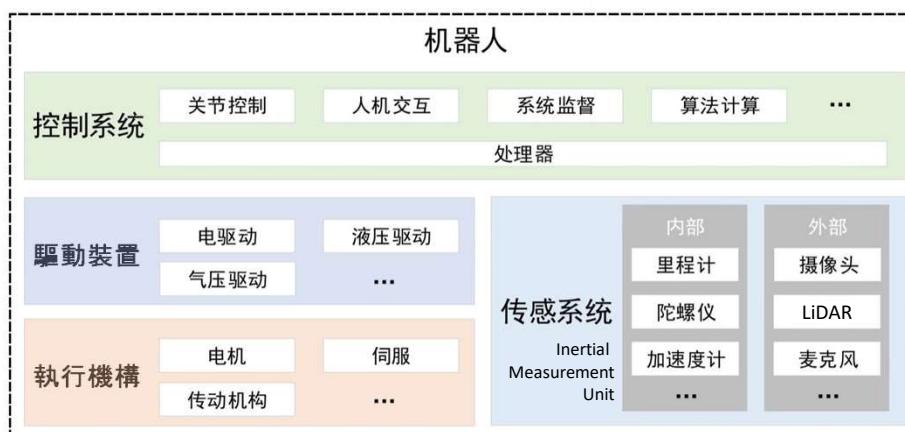


Define robot's tasks

5

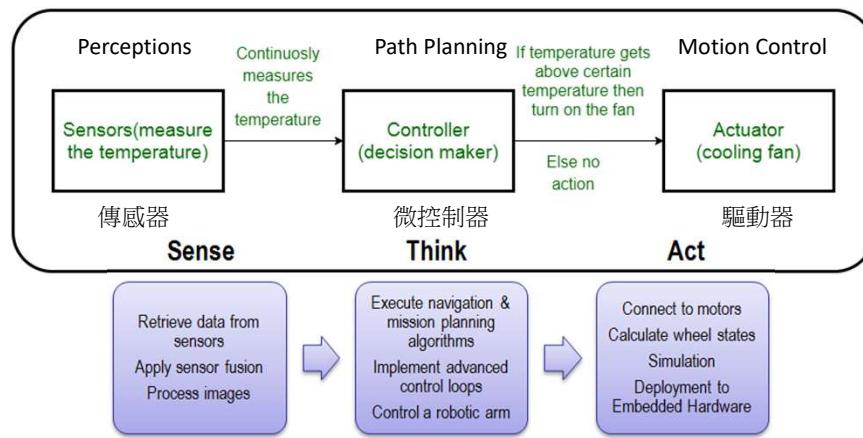


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Define robot's functions & behaviour

6

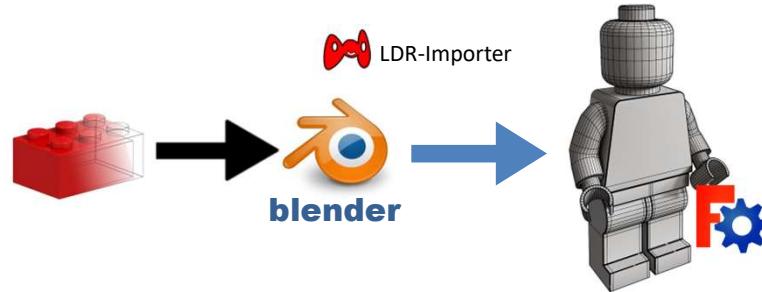


Robotics in physical computing

7

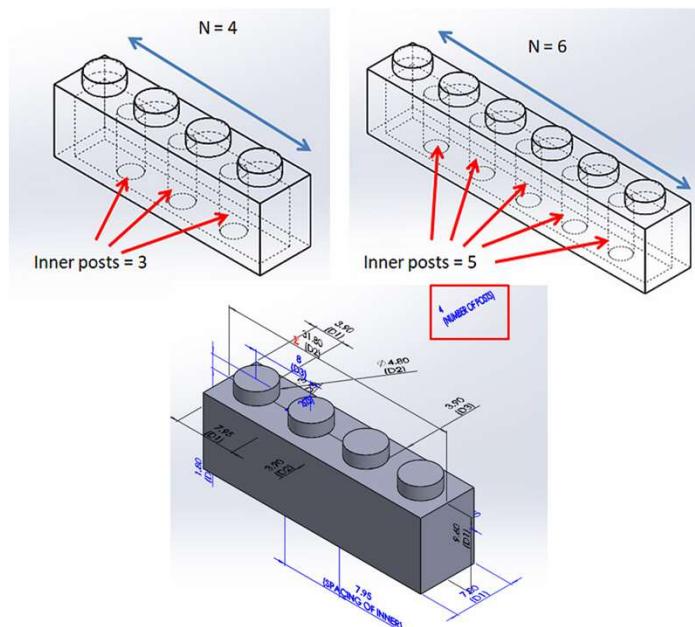


8



Parametric modeling

9

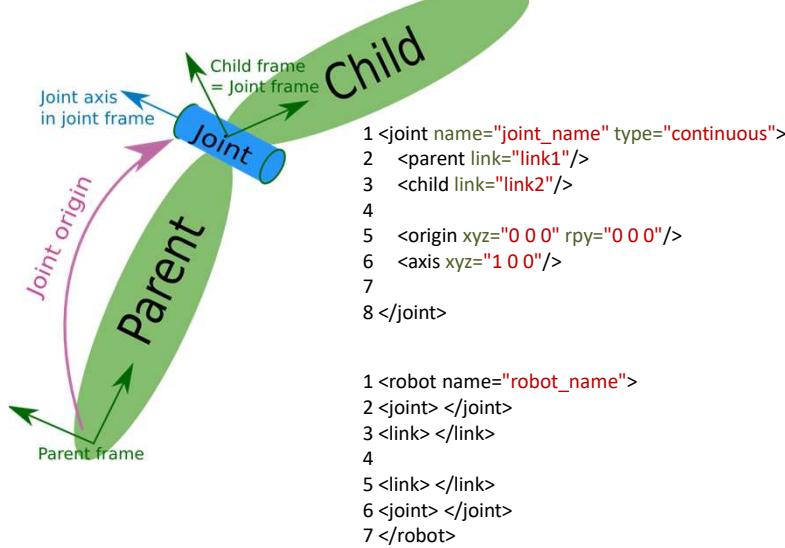


Parametric modeling

10



SEMTRON



URDF modeling

11

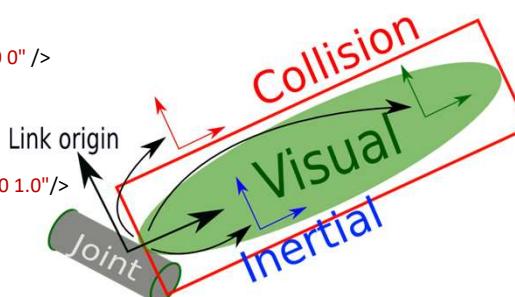
```

1 <link name="link_name">
2   <inertial>
3     <origin xyz="0 0 0.5" rpy="0 0 0" />
4     <mass value="1" />
5     <inertia ixx="100" ixy="0" ixz="0"
6       iyy="100" iyz="0"
7       izz="100" />
8   </inertial>
9
10  <visual>
11    <origin xyz="0 0 0" rpy="0 0 0" />
12    <geometry>
13      <box size="1 1 1" />
14    </geometry>
15    <material name="Cyan">
16      <color rgba="0 1 0 1.0" />
17    </material>
18  </visual>
19  <collision>
20    <origin xyz="0 0 0" rpy="0 0 0" />
21    <geometry>
22      <cylinder radius="1" length="0.5" />
23    </geometry>
24 </link>

```

$$\begin{pmatrix} \mathbf{ixx} & \mathbf{ixy} & \mathbf{ixz} \\ \mathbf{iyx} & \mathbf{iyy} & \mathbf{iyz} \\ \mathbf{izx} & \mathbf{izy} & \mathbf{izz} \end{pmatrix}$$

Inertia Tensor

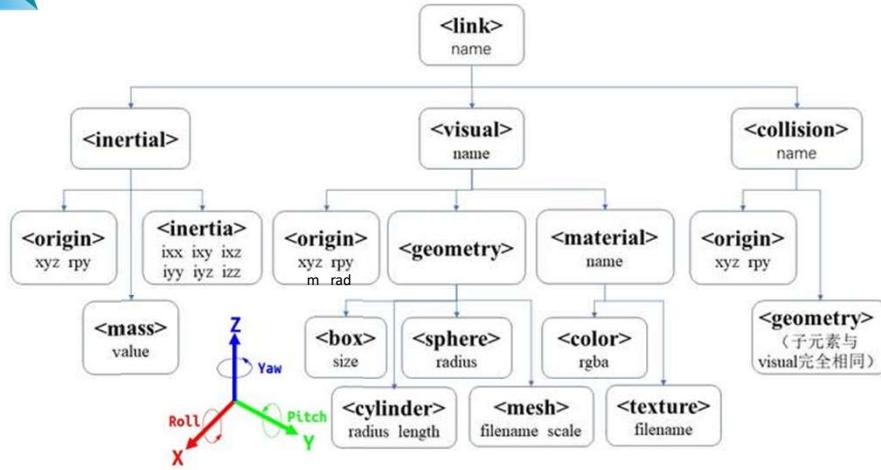


URDF modeling

12

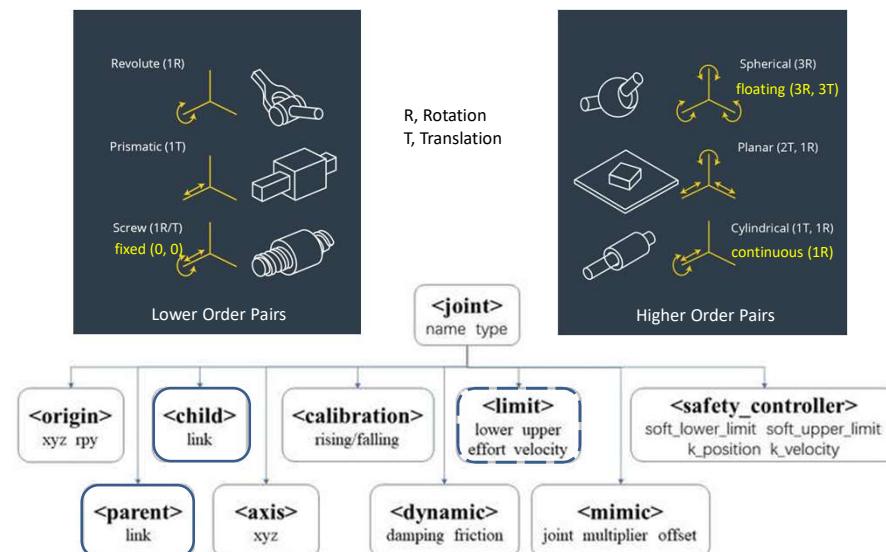


SEMTRO



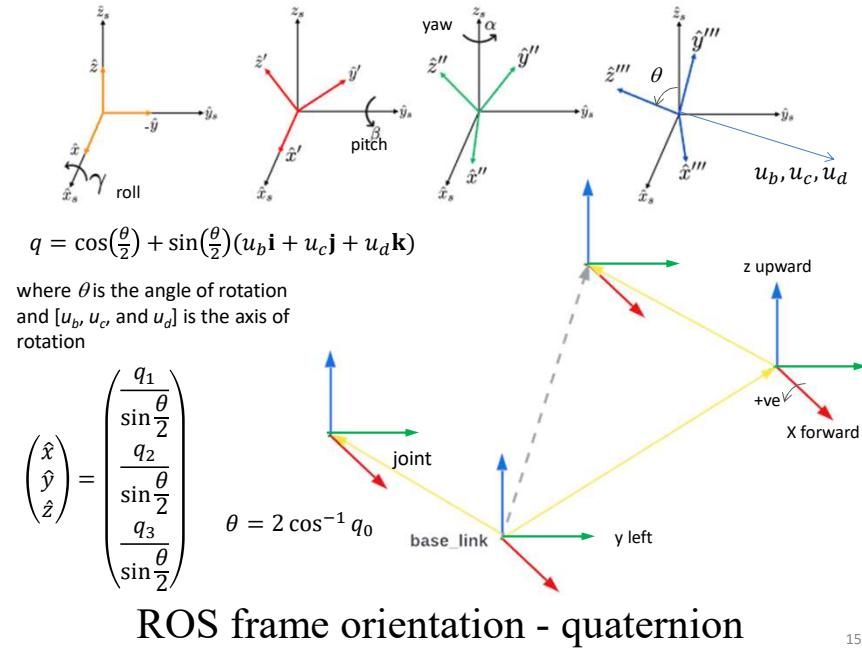
URDF modeling

13



URDF modeling

14



ROS frame orientation - quaternion

15

<https://articulatedrobotics.xyz/category/concept-design>



16

- ❑ Most robotics work are in teams include one who develops a CAD model of robot.
- ❑ Instead of crafting an URDF by hand it is possible to export an URDF model.
- ❑ Below is a list of available URDF exporters for a variety of CAD and 3D modeling software systems.

CAD Exporters

- [Fusion 360 URDF Exporter](#)
- [SolidWorks URDF Exporter](#)
- [ROS Workbench for FreeCAD](#)
- [OnShape URDF Exporter](#)
- [CREO Parametric URDF Exporter](#)

Other URDF Export Tools

- [Copellia Sim URDF Exporter](#)
- [Isaac Sim URDF Exporter](#)
- [Blender URDF Exporter](#)
- [Gazebo SDFFormat to URDF Parser](#)
- [SDF to URDF Converter in Python](#)
- The [Blender Robotics Tools](#) includes a tool to export [URDF files from Blender](#)

URDF from CAD models

17

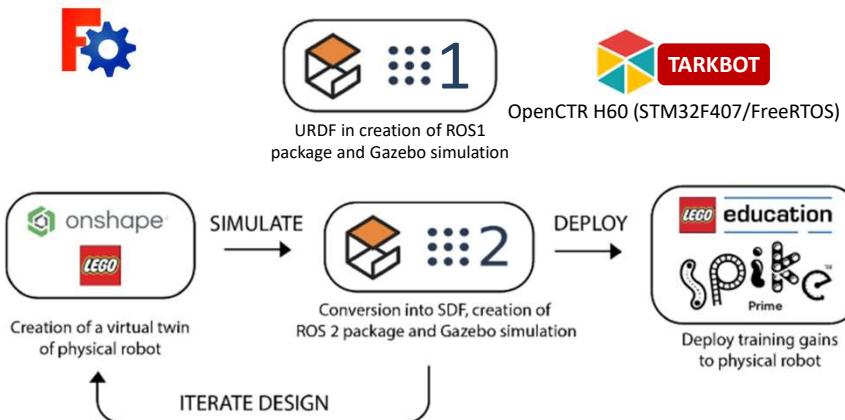


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Common Software

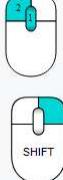
Common Hardware

https://download2.portableapps.com/portableapps/FreeCADPortable/FreeCADPortable_0.21.2.paf.exe



URDF from CAD models

18

Mode	Pan	Rotate	Zoom	Select
CAD (default)	 or 	 or 	 or 	 Multi select +CTRL
Touchpad	Hold Shift + drag	 		
Blender	Hold Shift + 			

FreeCAD mouse navigation

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<https://github.com/USeebi/Lesson0><https://github.com/drfenixion/freecad.overcross/wiki>

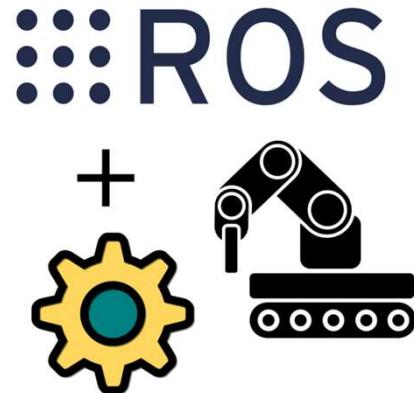
- **Ctrl** + **+** and **Ctrl** + **-** to zoom in and out, respectively.
- The arrow keys, **<** **>** **▲** **▼**, to shift the view left/right and up/down
- **Shift** + **<** and **Shift** + **>** to rotate the view by 90 degrees
- The numeric keys, **0** **1** **2** **3** **4** **5** **6**, for the seven standard views:
 Isometric,  Front,  Top,  Right,  Rear,  Bottom, and  Left
- **V** **O** will set the camera in  Orthographic view.
- While **V** **P** sets it in  Perspective view.
- **Ctrl** will allow you to select more than one object or element

FreeCAD keyboard navigation

20



Design Workspace in Robotics



21

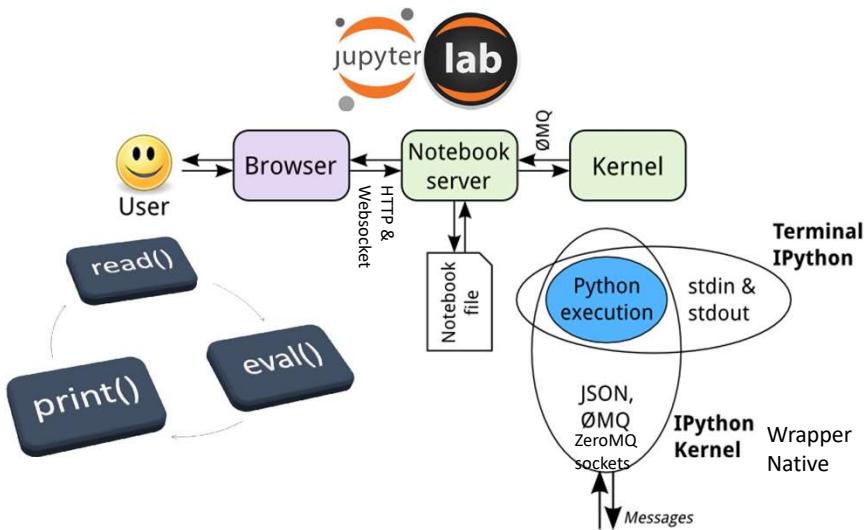


- CALENDAR
Timeliness
 be aware of the due dates and complete the tasks in accordance with the schedule stipulated by their teachers.
- PIE CHART
Good Planning
 break an extended task into smaller sub-parts and complete them in stages.
- COMPUTER
Good Record Keeping
 keep a complete record of their work, including drafts and backup copies of computer files.
- PERSON
Originality
 ensure the work they submit is their own, record the sources of information used and acknowledge them properly in their work.

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Proposed Python workspace

23

<https://robostack.github.io/index.html>

The screenshot shows a web-based Python workspace interface. On the left, a sidebar displays a file tree with notebooks like 'Lorenz.ipynb', 'Data.ipynb', 'Fasta.ipynb', 'Julia.ipynb', 'Cpp.ipynb', 'audio', 'images', and 'R.ipynb'. The main area has tabs for 'Launcher', 'README.md', 'Lorenz.ipynb', 'Terminal 1', 'Console 1', 'Data.ipynb', and 'Python 3 (ipykernel)'. The 'Lorenz.ipynb' tab is active, showing code to import matplotlib and ipywidgets, and a plot of the Lorenz attractor. The 'Output View' shows variables sigma=10.00, beta=2.67, rho=28.00, and the Lorenz plot. The 'ipykernel' tab shows the source code for 'lorenz.py'.

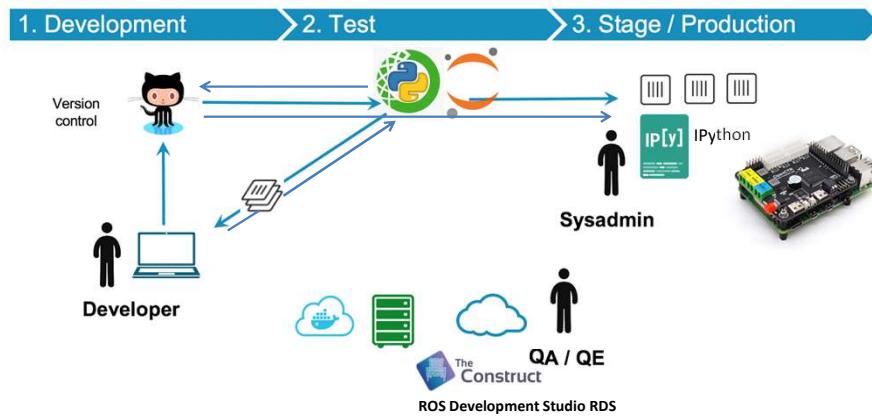
```

1 from matplotlib import pyplot as plt
2 from mpl_toolkits.mplot3d import Axes3D
3 import numpy as np
4 from scipy import integrate
5
6 def solve_lorenz(sigma=10.0, beta=8./3, rho=28.0):
7     """Plot a solution to the Lorenz differential
    equations."""
8
9     max_time = 4.0
10    N = 30
11
12    fig = plt.figure()
13    ax = fig.add_axes([0, 0, 1, 1], projection='3d')
14    ax.axis('off')

```

Proposed Python workspace

24



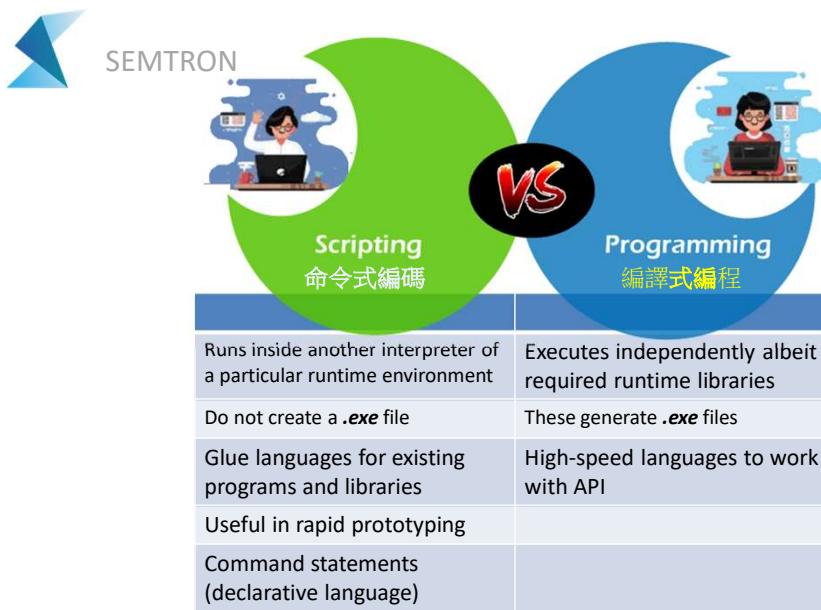
Proposed CI/CD workflow

25



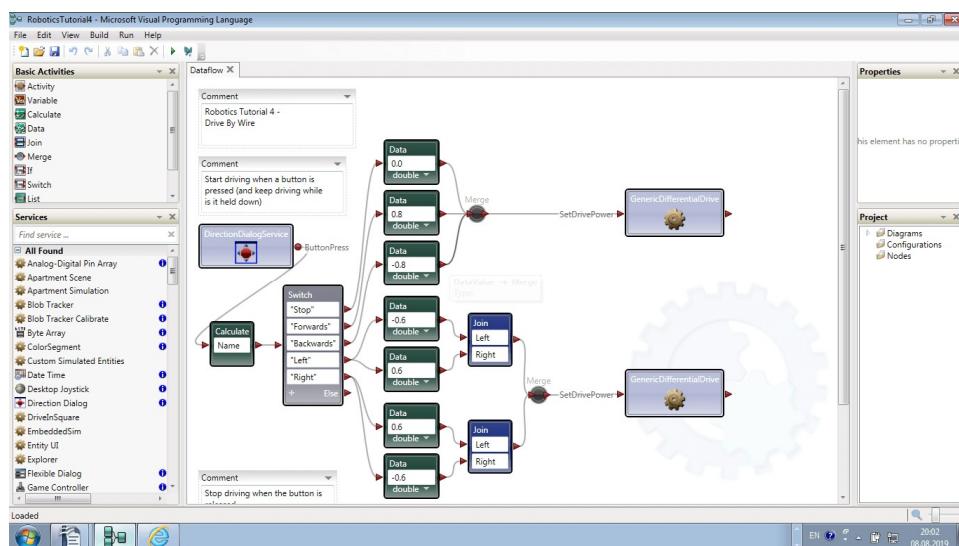
⌘ P #Show all commands	⌘ E #Explorer	⌘ D #Debug	⌘ H #Replace in files
⌘ P #Show files	⌘ B #Toggle sidebar	⌘ Y #Debug console	⌘ F #Find in files
⌘ M #Problems	⌘ U #Output	⌘ X #Extensions	⌃ ⌘ F #Find
VS CODE CHEATSHEET			
⌃ ⌘ F #Replace	F5 #Start	⌃ F5 #Stop	⌃ ⌘ F5 #Restart
⌃ J #Toggle panel	F11 #Step into		
⌃ F5 #Start without debugging	F9 #Toggle breakpoint	⌃ ⌘ D #Debug sidebar	
⌃ K U #Close unmodified	F10 #Step over	⌃ F11 #Step out	⌃ ⌘ Y #Debug panel
⌃ KW #Close all	⌃ KF #Close folder	⌃ ⌘ V #Open Markdown prev.	⌃ K Z #Zen mode

26



Python scripting

27

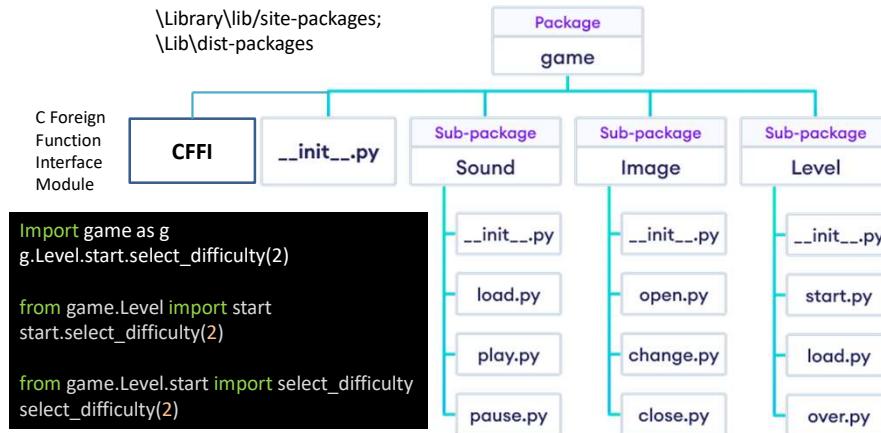


Visual scripting

28



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Packages are a way of structuring Python's module namespace by using "dotted module names".

Python packages

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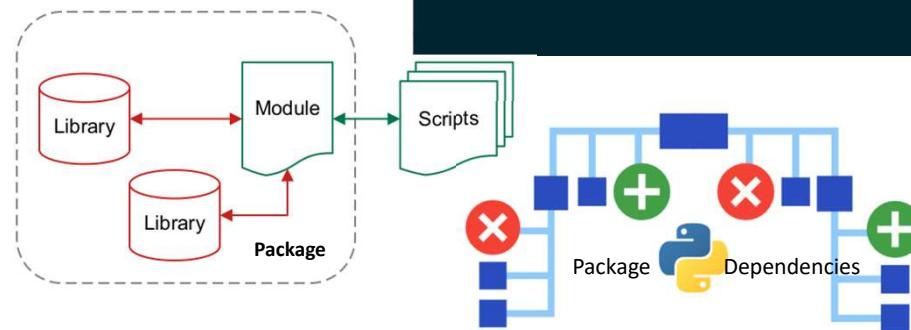


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A module is a file containing Python definitions & statements and use them in a script or in an interactive instance of the interpreter. The file name is the module name with the suffix .py appended.

```

$ cat hello_world.py
#!/bin/env python
print("Hello world!")
$ chmod +x hello_world.py
$ ./hello_world.py
Hello world!
$ 
$ python hello_world.py
Hello world!
$ 
  
```



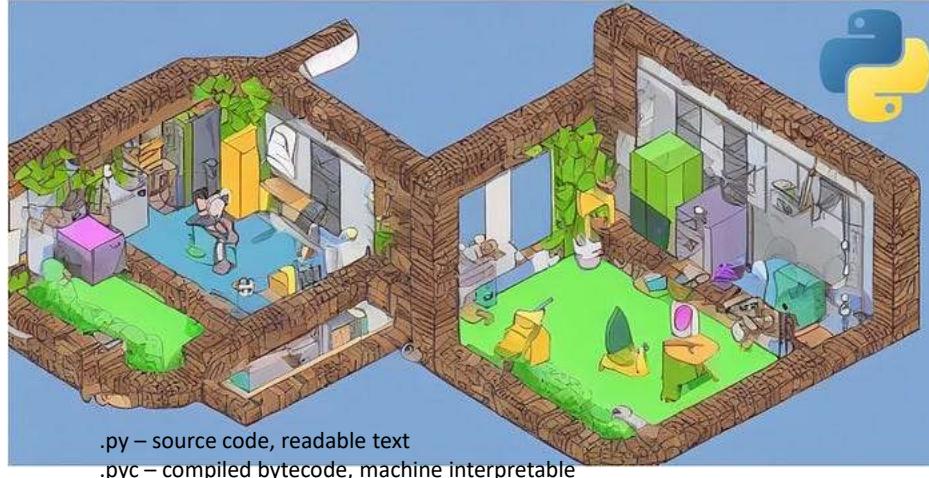
Python packages

30



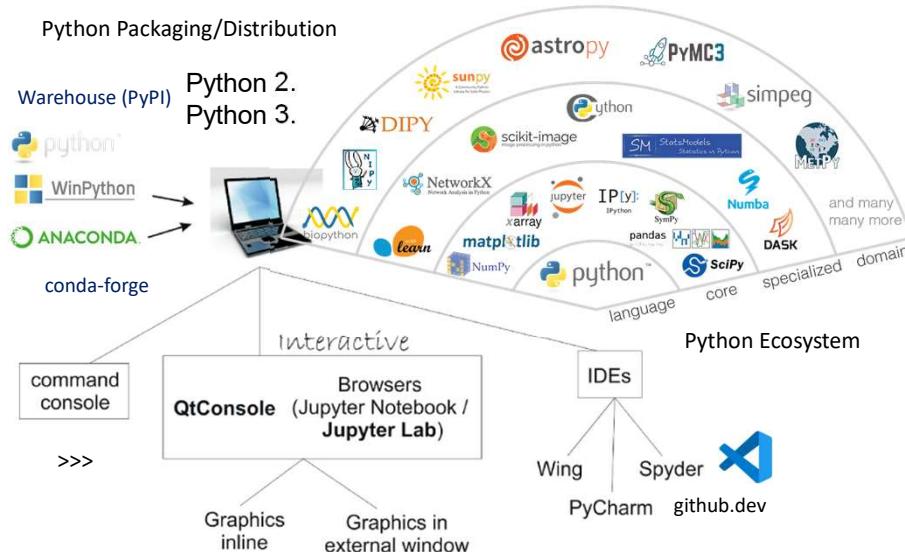
SEMTRO

```
$ conda env export > environment.yml
$ conda env create -f environment.yml
```



Python virtual environment

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Python robotic development

32

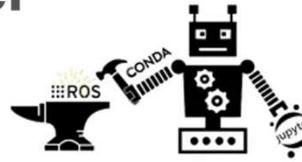


SEMTRO

binder

RoboStack

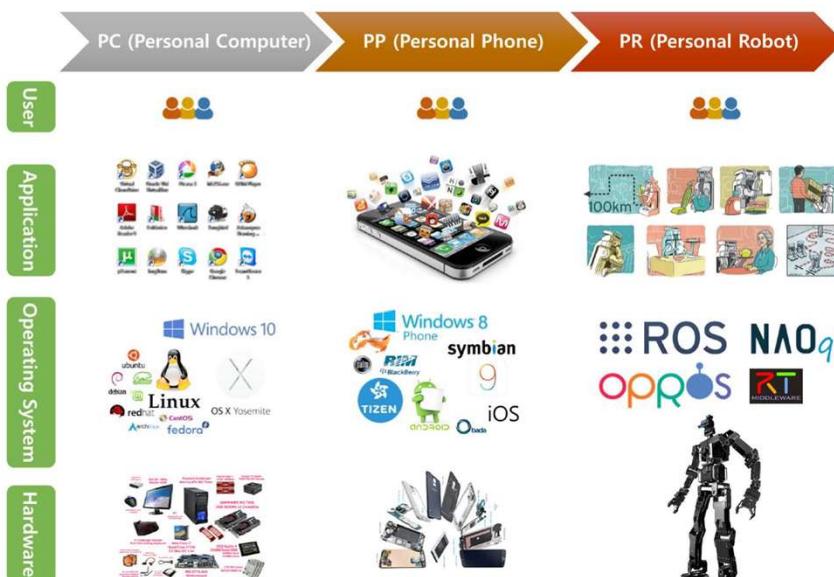
**Using the Robot Operating System alongside
the Conda and Jupyter Data Science Ecosystems**



- ✓ ROS on *any* platform: + +
- ✓ Easy installation of ROS side-by-side with PyTorch , Tensorflow & many more
- ✓ No root access required – install ROS on shared workstations & high-performance computers
- ✓ Reproducible environments + reproducible robotics research
- ✓ RViz-like visualizations in the browser *without* a ROS installation
- ✓ Control your robot in Jupyter Notebooks & ROS integration with JupyterLab

Python robotic development

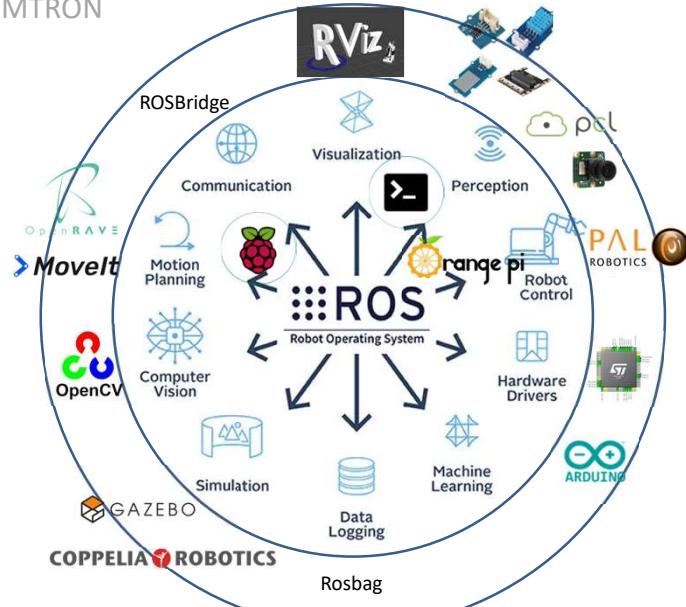
33

**Operating System**

34



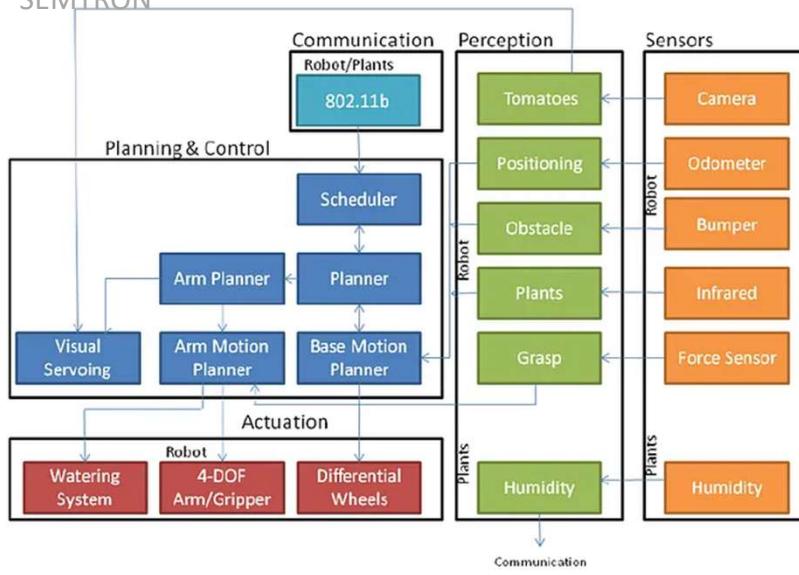
SEMTRON



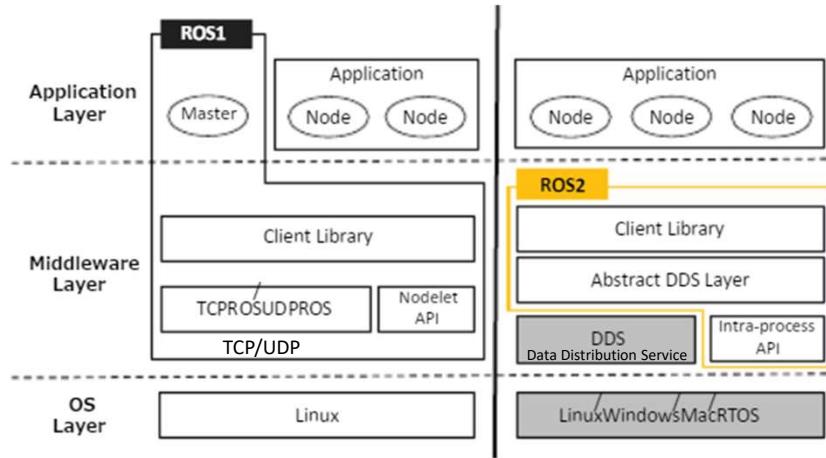
35



SEMTRON

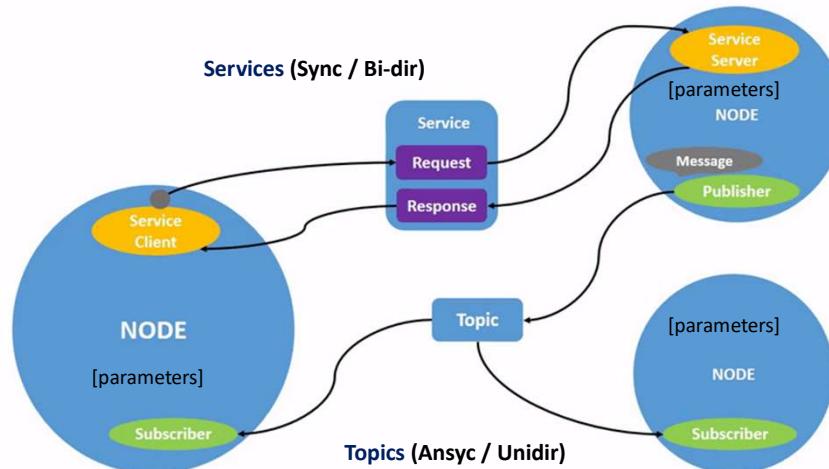


36



Robot Operating System

37

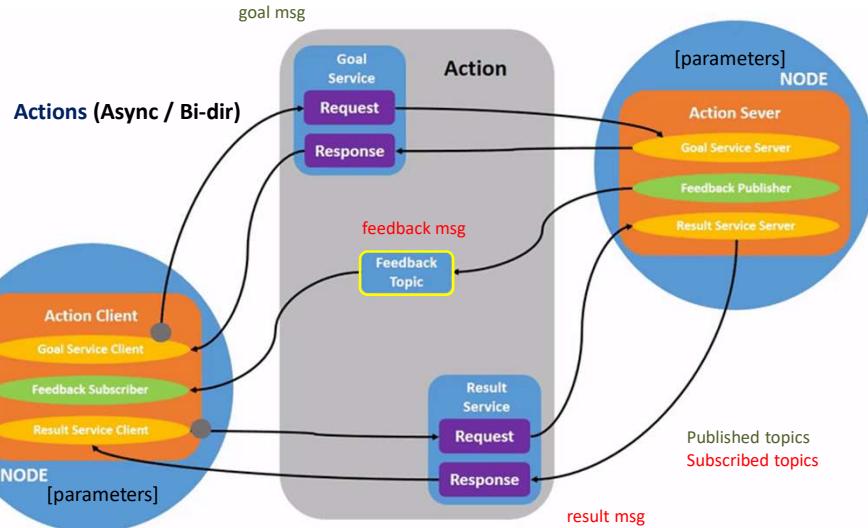


Robot Operating System

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SEMTRO

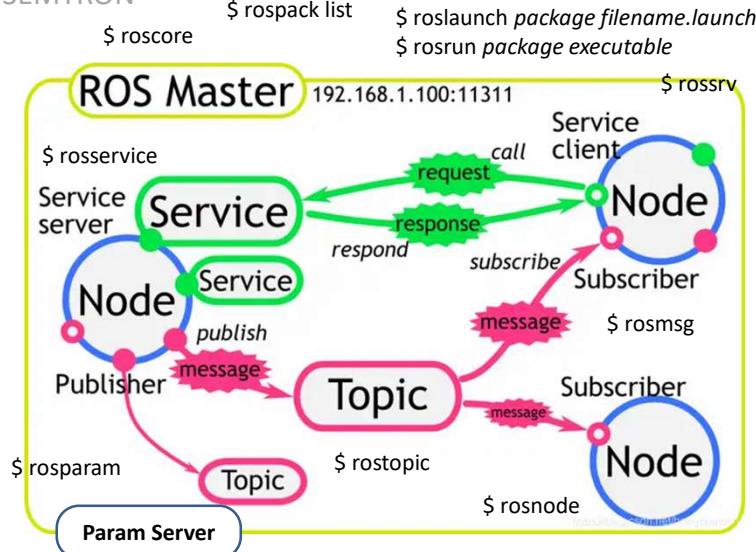


Robot Operating System

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Robot Operating System

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SEMTRO

```

### activate ros_noetic env
$ conda activate K:\Miniconda3\envs\ros_noetic
$ roscore

### launch ros1 cli
$ rostopic list

### launch rviz GUI
$ rosrun rviz rviz

### launch gazebo GUI
$ gazebo --verbose

### launch a demo node talker
$ roscd rospy_tutorials
$ 001_talker_listener/talker

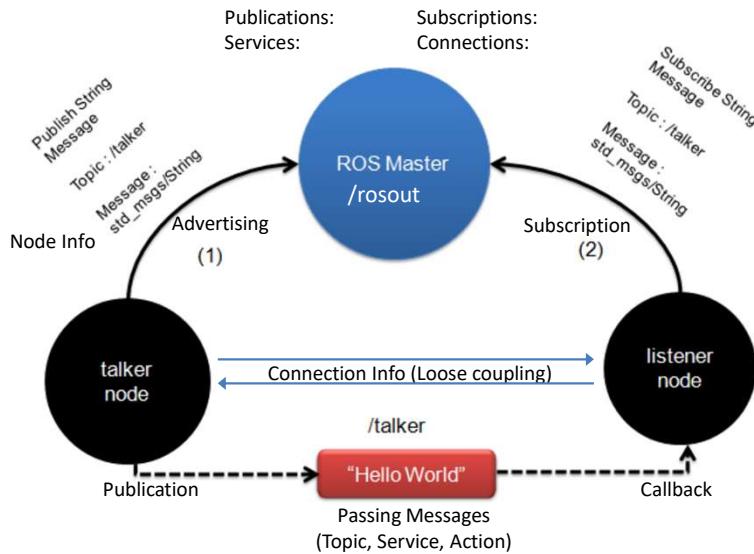
### from another terminal activate the ros_noetic env and launch a
demo listener
$ rosrun rospy_tutorials listener

```

41

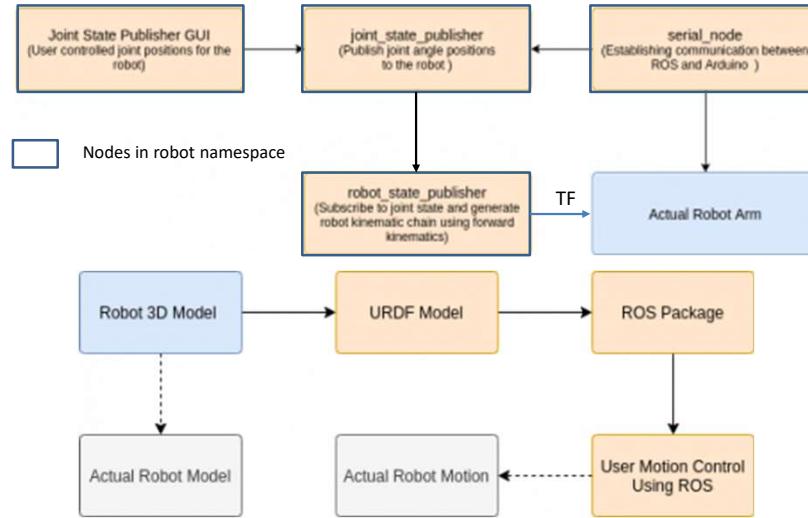


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ROS nodes and messages

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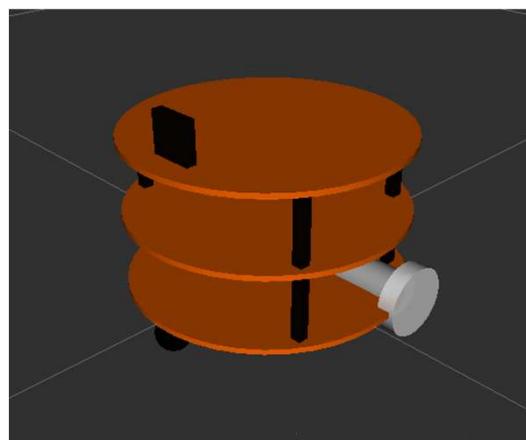
ROS URDF models

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ROS机器人开发实践 – 胡春旭
https://github.com/peijian1998/ros_exploring



ROS URDF models

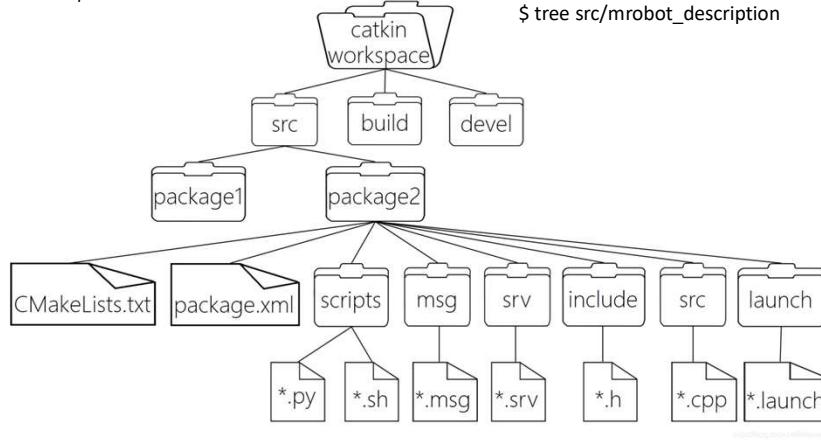
44



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```
$ rospack
$ roscl
```

```
$ cd ~/catkin_ws
$ tree src/mrobot_description
```



ROS applications

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SEMTRO

SENSE
THINK
ACT
PACKAGE

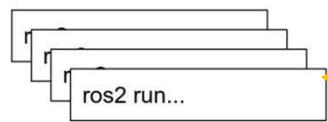
SENSOR NODE

COMPUTE NODE

MOTOR NODE

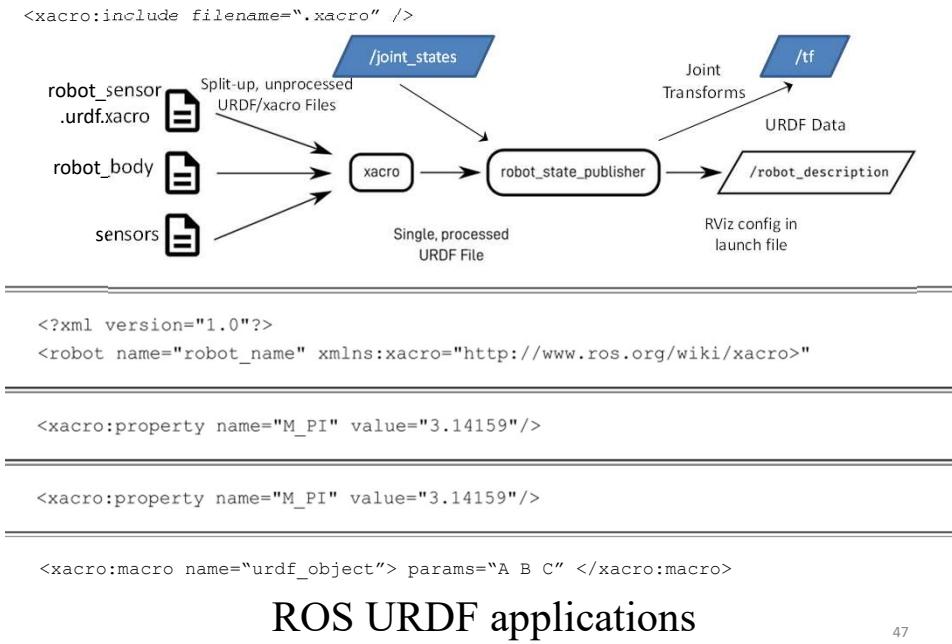
ROBOT NODE

PARAMS PACKAGE



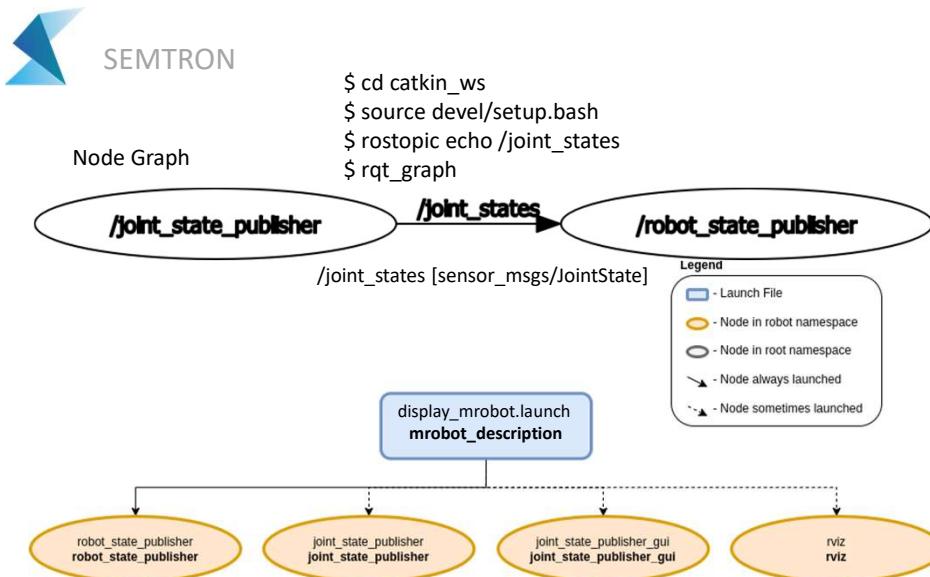
ROS applications

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ROS URDF applications

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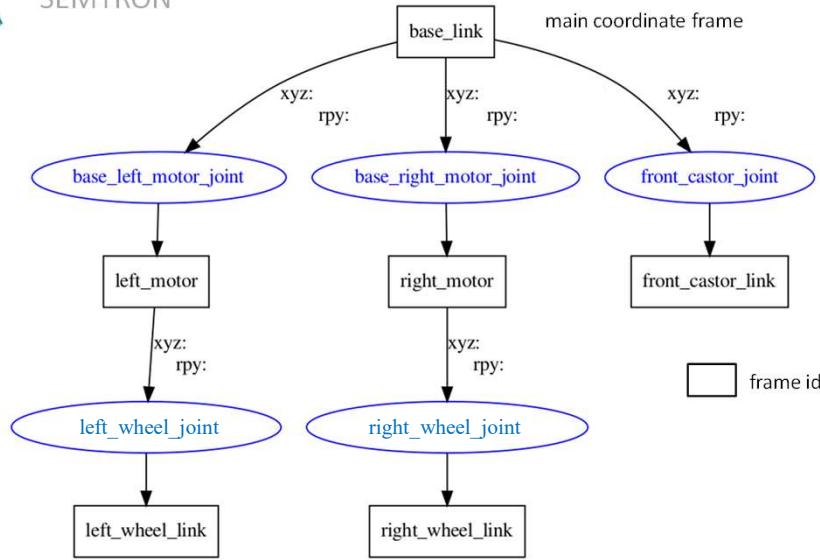


ROS visualizations

48



SEMTRO



ROS URDF models

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```

<link name="base_link">
  <visual>
    <origin xyz=" 0 0 0" rpy="0 0 0" />
    <geometry>
      <cylinder length="0.005" radius="0.13"/>
    </geometry>
    <material name="yellow">
      <color rgba="1 0.4 0 1"/>
    </material>
  </visual>
  <collision>
    <origin xyz=" 0 0 0" rpy="0 0 0" />
    <geometry>
      <cylinder length="0.005" radius="0.13"/>
    </geometry>
  </collision>
  <inertial>
    <mass value="2" />
    <origin xyz="0 0 0" />
    <inertia ixx="0.01" ixy="0.0" ixz="0.0"
             iyy="0.01" iyz="0.0" izz="0.5" />
  </inertial>
</link>                                         display_mrobot_chassis_withPhy_urdf.launch
<launch>
  <param name="robot_description" textfile="$(find
mrobot_description)/urdf/mrobot_chassis_withPhy.urdf" />

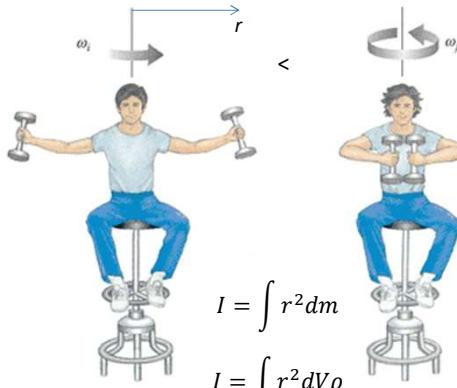
```



50



SEMTRON



$$I = \begin{bmatrix} I_{xx} & I_{xy} & I_{xz} \\ I_{yx} & I_{yy} & I_{yz} \\ I_{zx} & I_{zy} & I_{zz} \end{bmatrix}$$

$$I_{xx} = \int \rho(\hat{y}^2 + \hat{z}^2)dV$$

$$I_{xy} = \int \rho(\hat{x}\hat{y})dV$$

I_{xx} **moment of inertia** about the x-axis
 I_{xy} **product of inertia** about a pair of given perpendicular axes

center of gravity $I \triangleq \iiint_V r^2 \rho(r) dV$

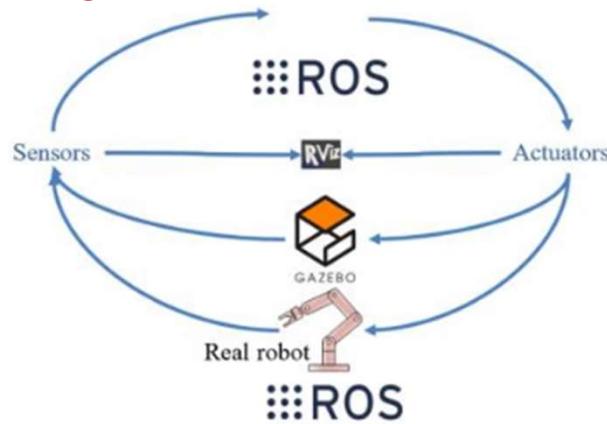
Physical properties in ROS URDF

51



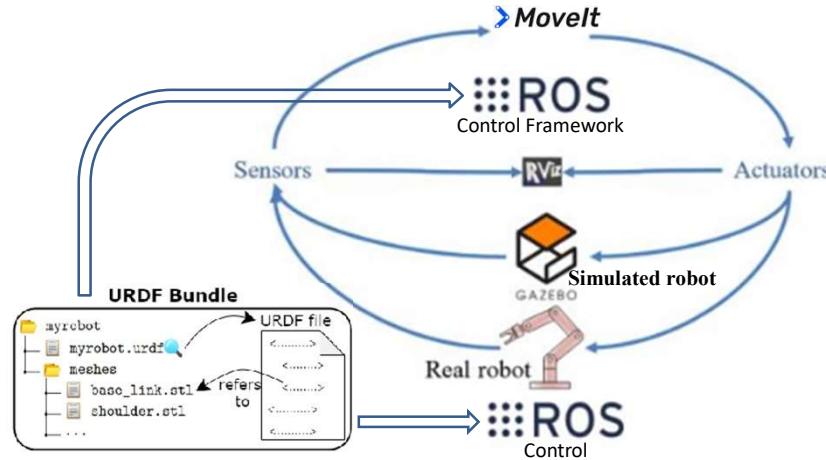
SEMTRON

Design Simulations in Robotics

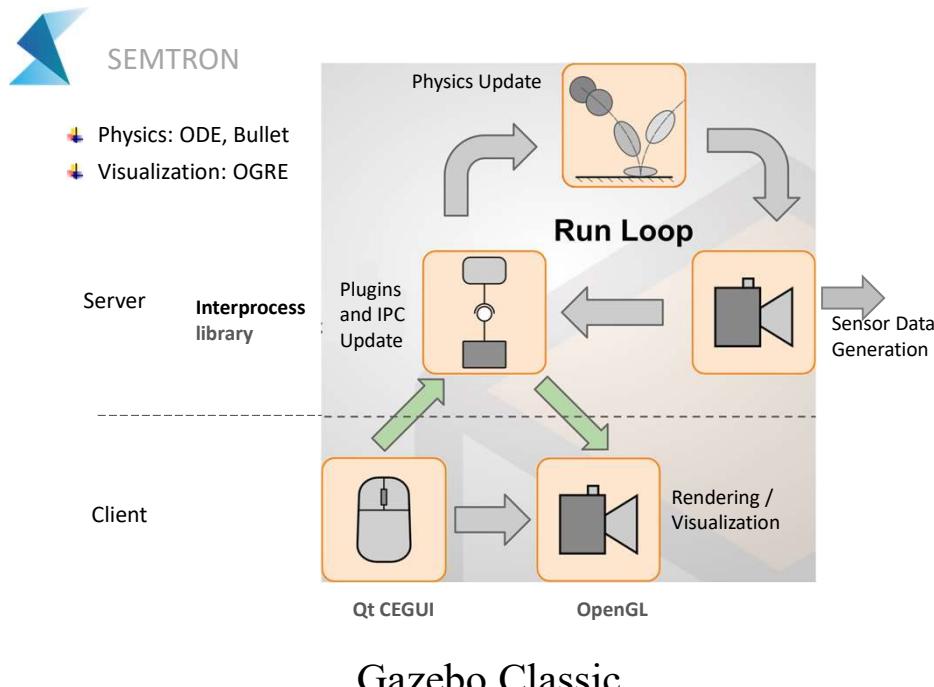


52

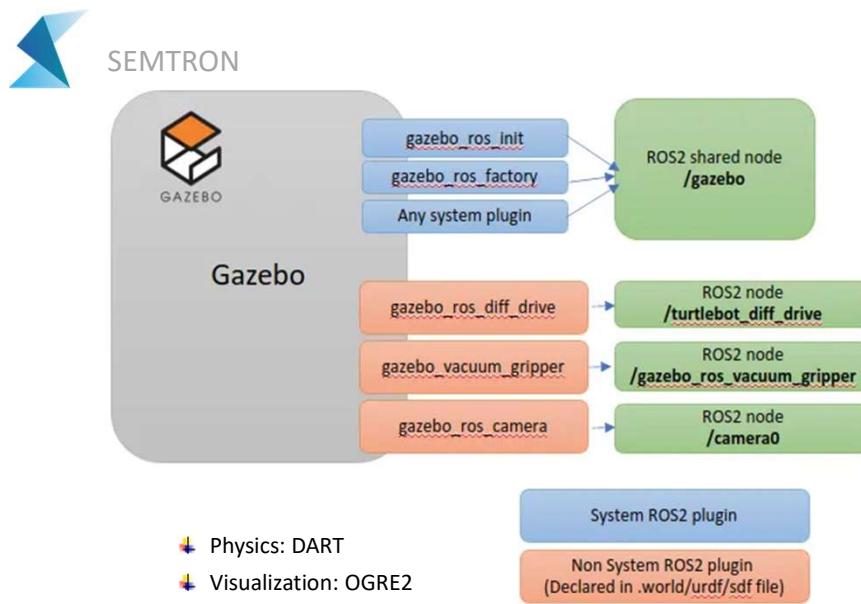
“ . . . RViz shows you what the robot thinks is happening, while Gazebo shows you what is really happening.”



53

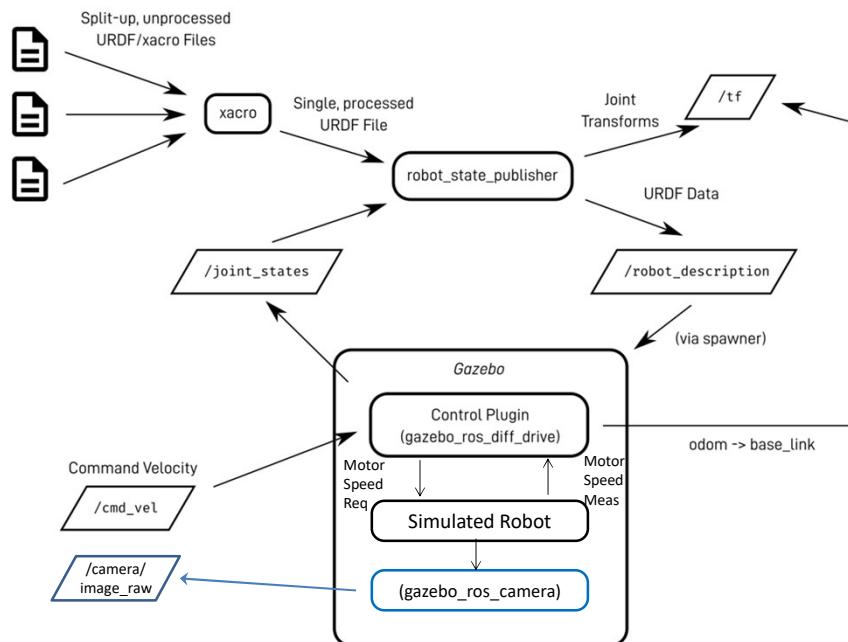


54



Gazebo Ignition

55

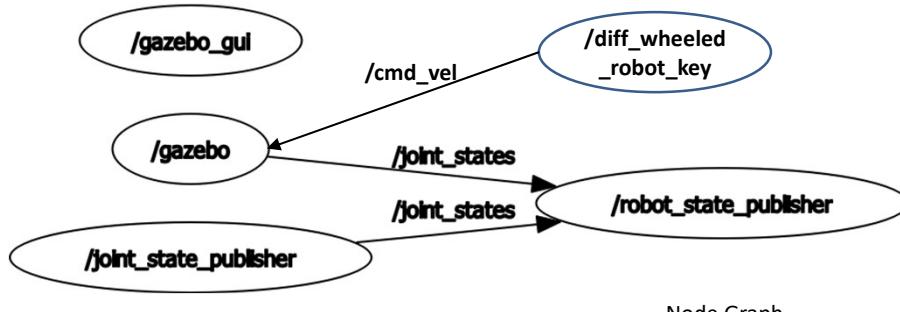


56



SEMTRO

```
$ roslaunch mrobot_gazebo view_mrobot_with_camera_gazebo.launch
$ roslaunch diff_wheeled_robot_control keyboard_teleop.launch
$ rostopic echo /cmd_vel
```



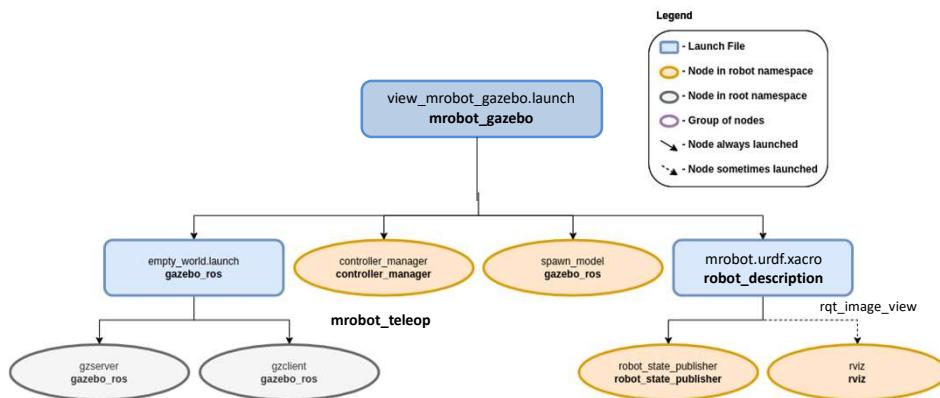
Node Graph

ROS simulation

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SEMTRO



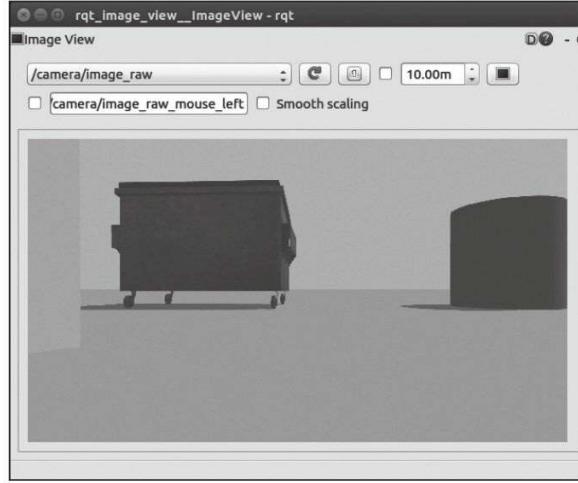
ROS simulation

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SEMTRO

```
view_mrobot_with_camera_gazebo.launch
<node name="rviz" pkg="rviz" type="rviz" args="-d $(find
mrobot_description)/config/mrobot.rviz" required="true" />
```

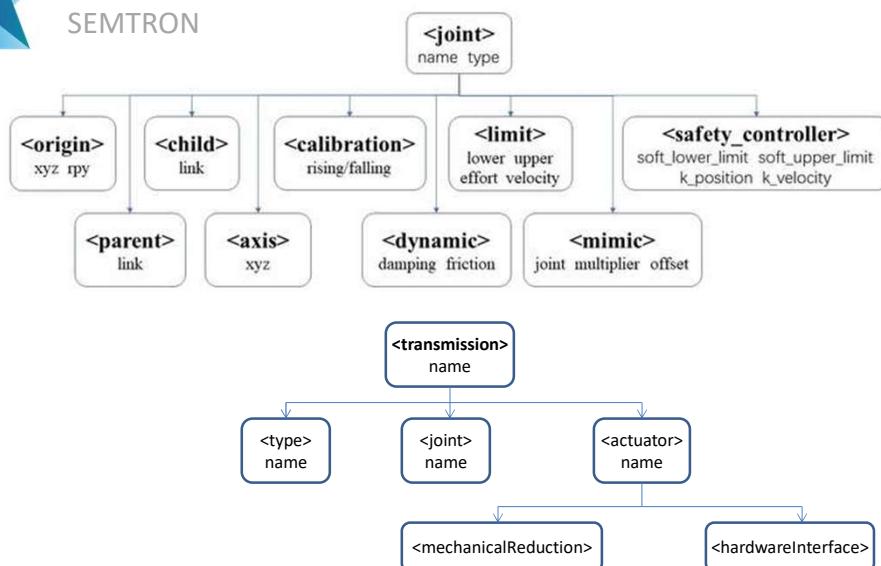


ROS simulation

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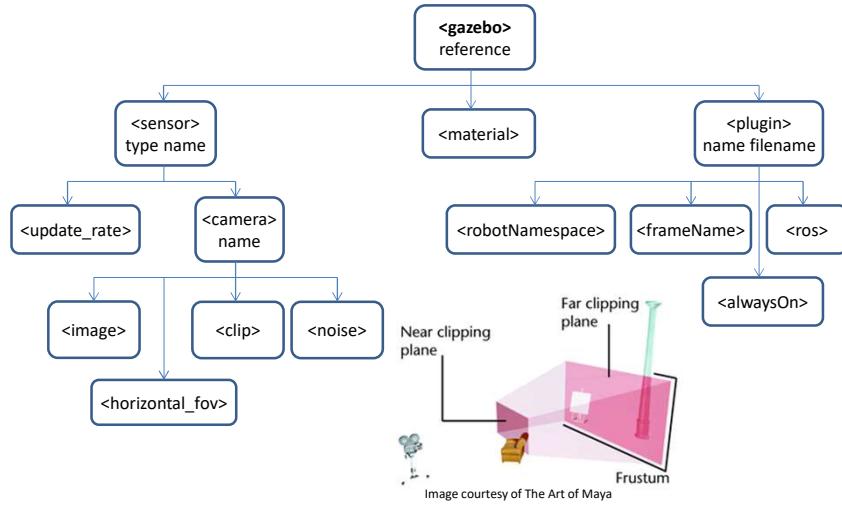


SEMTRO



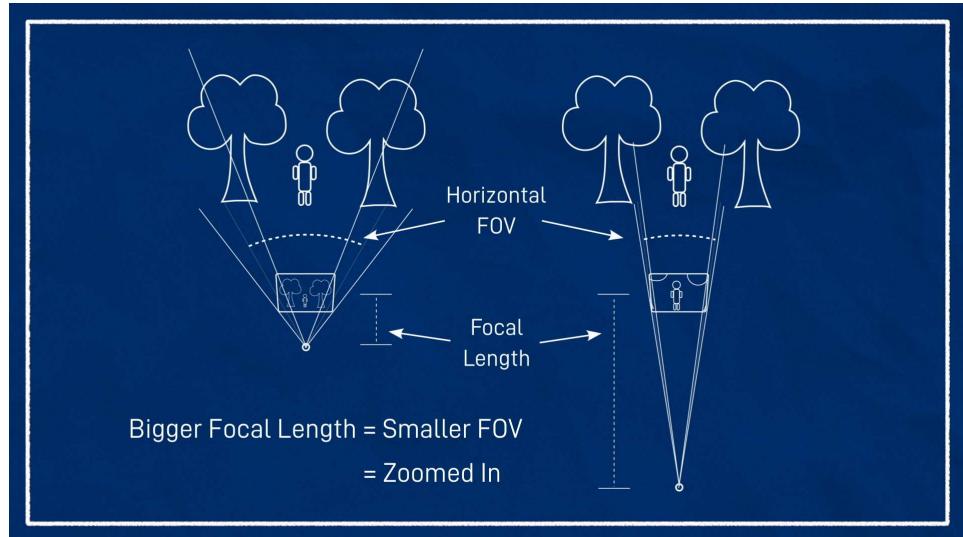
Gazebo simulation

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Gazebo simulation

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Gazebo simulation

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Homework

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ROS packages Gazebo Plugin Deprecated from simulator_gazebo

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https://repo.anaconda.com/miniconda/Miniconda3-py311_24.5.0-0-Windows-x86_64.exe

```
>Downloads\Miniconda3-py311_24.5.0-0-Windows-x86_64.exe
/InstallationType=JustMe /AddToPath=0 /RegisterPython=0 /NoRegistry=1 /S
/D=K:\Miniconda3\py311
```

```
(base) > conda install mamba -c conda-forge
(base) > conda install git
(base) > mamba create -p K:\Miniconda3\envs\ros_noetic python=3.11
(base) > mamba activate K:\Miniconda3\envs\ros_noetic
(ros_noetic)
(ros_noetic) > conda config --env --add channels conda-forge
(ros_noetic) > conda config --env --add channels robostack-staging
(ros_noetic) > conda config --env --remove channels defaults
(ros_noetic) > mamba install ros-noetic-desktop ros-noetic-gazebo-ros
(ros_noetic) > mamba install ros-noetic-gazebo-plugins ros-noetic-gazebo-ros-pkgs ros-noetic-
gazebo-ros-control ros-noetic-rqt-controller-manager ros-noetic-xacro ros-
noetic-move-base
(ros_noetic) > mamba deactivate
(base) > mamba activate K:\Miniconda3\envs\ros_noetic
```

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```
$ rosrun teleop_twist_keyboard teleop_twist_keyboard.py
```

