

10 TF release and monitoring

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10.1 tf function package

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10.1.2 Use steps

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10.1 tf function package

10.1.1 tf is a function package that allows users to track multiple coordinate systems over time. It uses a tree data structure to buffer and maintain the coordinate transformation relationship between multiple coordinate systems according to time, which can help developers at any time., to complete coordinate transformations such as points and vectors between coordinate systems.

10.1.2 Use steps

1. monitor tf transformation

Receive and cache all coordinate system transformation data published in the system, and query the required coordinate transformation relationship from it.

2. broadcast tf transformation

Broadcasts the coordinate transformation relationship between coordinate systems to the system. There may be multiple broadcasts of tf transforms of different parts in the system. Each broadcast can directly insert the coordinate transformation relationship into the tf tree without synchronization.

10.2 Programming implementation of tf coordinate system broadcasting and monitoring**

10.2.1 Create and compile function packages

```
cd ~/catkin_ws/src
catkin_create_pkg learning_tf rospy roscpp turtlesim tf
cd ..
catkin_make
```

10.2.2 how to implement a tf broadcaster

1. define tf broadcaster(TransformBroadcaster);
2. initialize tf data, create coordinate transformation value;
3. publish coordinate transformation(sendTransform);

10.2.3 How to implement a tf listener

1. define TF listener(TransformListener);
2. find coordinate transformation(waitForTransform, lookupTransform)

10.2.4 C++ language implements tf broadcaster

1. In the src folder of the function package learning_tf, create a c++ file(the file suffix is .cpp) and name it turtle_tf_broadcaster.cpp
2. copy and paste the program code below into the turtle_tf_broadcaster.cpp file

```
#include <ros/ros.h>
#include <tf/transform_broadcaster.h>
#include <turtlesim/Pose.h>

std::string  turtle_name;

void poseCallback(const turtlesim::PoseConstPtr & msg)
{
    static tf::TransformBroadcaster br; // create a broadcaster for tf

    // initialize tf data
    tf::Transform transform;
    transform.setOrigin(tf::Vector3(msg->x, msg->y, 0.0)); //set xyz
coordinates
    tf::Quaternion q;
    q.setRPY(0, 0, msg->theta); //Set Euler angle: rotate with x-axis, y-axis,
z-axis
    transform.setRotation(q);

    br.sendTransform(tf::StampedTransform(transform, ros::Time::now() "world",
turtle_name)); // broadcast tf data between world and turtle coordinate system
}

int main(int argc, char** argv)
{
    ros::init(argc, argv, "turtle_world_tf_broadcaster"); // initialize the ROS
node
```

```

if (argc != 2)
{
    ROS_ERROR("Missing a parameter as the name of the turtle!");
    return -1;
}

turtle_name = argv [ 1 ]; // input argument as turtle name

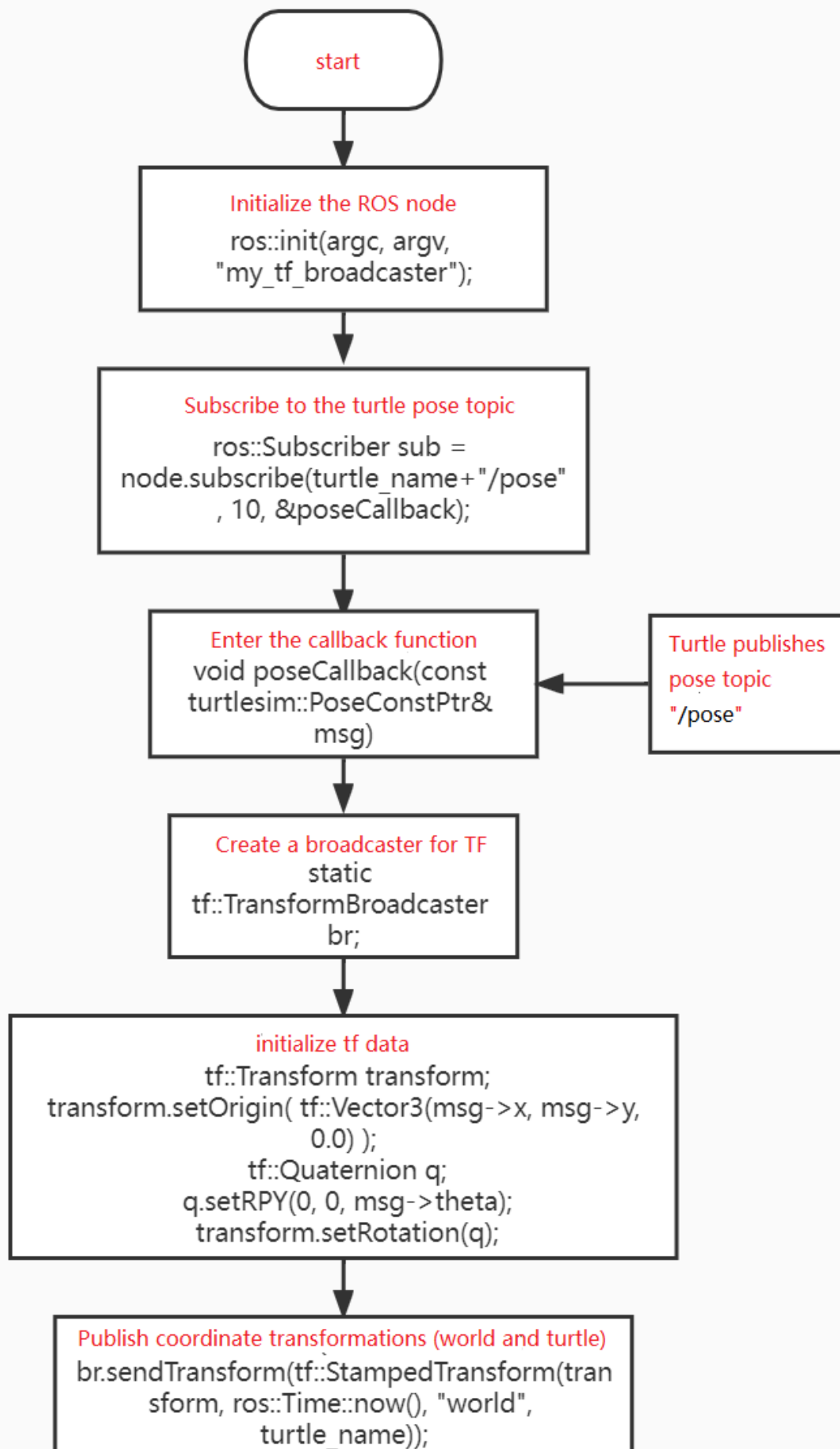
// Subscribe to the turtle's pose topic/pose
ros::NodeHandle node;
ros::Subscriber sub = node.subscribe(turtle_name + "/pose", 10, &
poseCallback);

    // loop waiting for the callback function
    ros::spin();

    return 0;
};

```

3. program flow chart



First of all, first subscribe to the /pose pose topic of the little turtle. If there is a topic published, then enter the callback function. In the callback function, the tf broadcaster is first created, and then the tf data is initialized. The value of the data is the data transmitted by the subscription/pose topic. Finally, the transformation of the small turtle to the world coordinates is released through br.sendTransform. Here is the function sendTransform. There are 4 parameters, the first parameter represents the coordinate transformation of type tf::Transform(that is, the tf data initialized before) the second parameter is the timestamp, the third and fourth are the source coordinate system of the transformation and target coordinate system.

10.2.4 C++ language implements tf listener

1. In the src folder of the function package learning_tf, create a c++ file(the file suffix is .cpp) and name it turtle_tf_listener.cpp
2. copy and paste the program code below into the turtle_tf_listener.cpp file

```
/**
 * This routine monitors tf data, and calculates and issues the speed command of
 * turtle2
 * turtle2->turtle1 = world->turtle*world->turtle2
 */

#include <ros/ros.h>
#include <tf/transform_listener.h>
#include <geometry_msgs/Twist.h>
#include <turtlesim/Spawn.h>

int main(int argc, char** argv)
{
    ros::init(argc, argv, "turtle1_turtle2_listener"); // initialize the ROS
    node

    ros::NodeHandle node; // create node handle

    // Request service to generate turtle2
    ros::service::waitForService("/spawn");
    ros::ServiceClient add_turtle = node.serviceClient < turtlesim::Spawn >
    ("/spawn");
    turtlesim::Spawn srv;
    add_turtle.call(srv);

    // Create a publisher that issues turtle2 speed control commands
    ros::Publisher vel = node.advertise < geometry_msgs::Twist >
    ("/turtle2/cmd_vel", 10);

    tf::TransformListener listener; // Create a listener for tf

    ros::Rate rate(10.0);

    while (node.ok())
    {
        // Get tf data between turtle1 and turtle2 coordinate systems
        tf::StampedTransform transform;
        try
        {
```

```

        listener.waitForTransform("/turtle2", "/turtle1", ros::Time(0)
ros::Duration(3.0));
        listener.lookupTransform("/turtle2", "/turtle1", ros::Time(0)
transform);
    }
    catch (tf::TransformException & ex)
    {
        ROS_ERROR("%s", ex.what());
        ros::Duration(1.0).sleep();
        continue;
    }

    // According to the positional relationship between turtle1 and turtle2
coordinate systems, through mathematical formulas, the angular velocity and
linear velocity are obtained, and the speed control command of turtle2 is issued

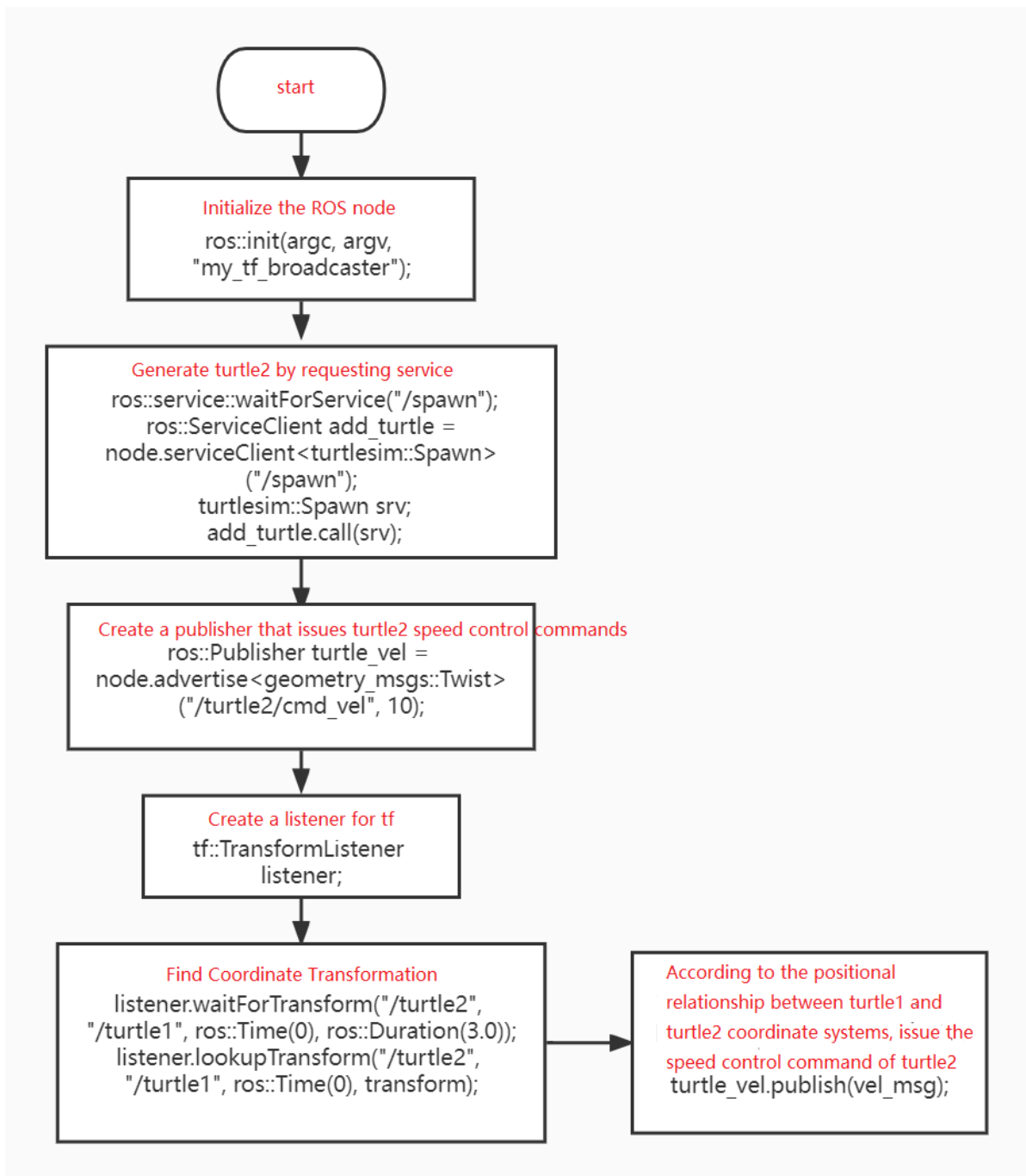
    geometry_msgs::Twist  turtle2_vel_msg;

    turtle2_vel_msg.angular.z  =  6.0  *  atan2(transform.getOrigin(). y()
transform.getOrigin(). x());
    turtle2_vel_msg.linear.x  =  0.8  *  sqrt(pow(transform.getOrigin(). x()
2)  +
pow(transform.getOrigin(). y()  2));
    vel.publish(turtle2_vel_msg);

    rate.sleep();
}
return 0;
};

```

3. program flow chart



4. code analysis

First, generate another small turtle turtle2 through a service call, and then create a turtle2 speed control publisher; then create a listener to monitor and find the left transformation of turtle1 and turtle2, which involves two functions `waitForTransform` and `lookupTransform`

`waitForTransform(target_frame, source_frame, time, timeout)`: The two frames represent the target coordinate system and the source coordinate system respectively, time represents the time to wait for the transformation between the two coordinate systems, because the coordinate transformation is a blocking program, so you need to set the timeout, indicating overtime time.

`lookupTransform(target_frame, source_frame, time, transform)`: Given the source coordinate system (source_frame) and the target coordinate system (target_frame) get the coordinate transformation (transform) of the specified time (time) between the two coordinate systems.

After `lookupTransform`, we get the result of the coordinate transformation, `transform`, and then get the values of x and y through `transform.getOrigin().y()` `transform.getOrigin().x()` and then get the angular velocity `angular.z` and line through mathematical operations `Speed linear.x`, finally released, let turtle2 do the movement.

10.2.5 Modify CMakeList.txt and compile

1. modify and modify CMakeList.txt

Modify the CMakeList.txt under the function package and add the following content

```
add_executable(turtle_tf_listener src/turtle_tf_listener.cpp)
target_link_libraries(turtle_tf_listener ${catkin_LIBRARIES})

add_executable(turtle_tf_broadcaster src/turtle_tf_broadcaster.cpp)
target_link_libraries(turtle_tf_broadcaster ${catkin_LIBRARIES})
```

2. compile

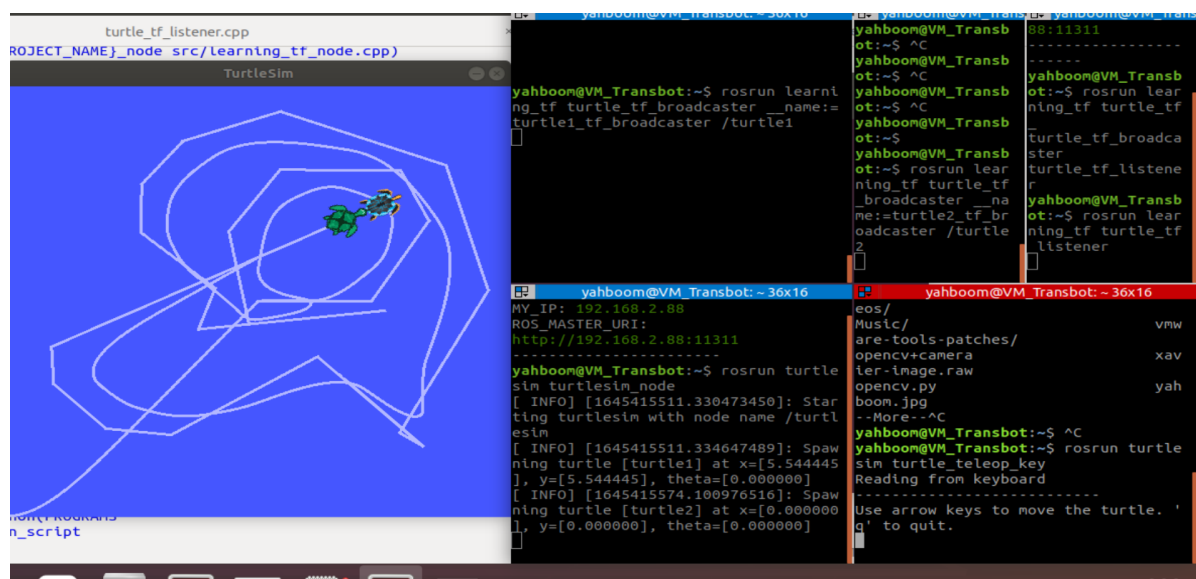
```
cd ~/catkin_ws
catkin_make
source devel/setup.bash #Environment variables need to be configured,
otherwise the system cannot find the running program
```

10.2.6 Demonstration of startup and running effects

1. start

```
roscore
roslaunch turtlesim turtlesim_node
roslaunch learning_tf turtle_tf_broadcaster __name:=turtle1_tf_broadcaster
/turtle1
roslaunch learning_tf turtle_tf_broadcaster __name:=turtle2_tf_broadcaster
/turtle2
roslaunch learning_tf turtle_tf_listener
roslaunch turtlesim turtle_teleop_key #Open the turtle keyboard control program
to control the turtle movement
```

2. effect display



3. program description

After starting roscore, open the small turtle node, and a small turtle will appear in the terminal; then we publish two tf transformations, turtle1->world, turtle2->world, because to know the change between turtle2 and turtle1, then You need to know the transformation between them and the world; then, open the tf listener program, you will find that the terminal has generated another small turtle, turtle2, and turtle2 will move to turtle1; then, we open the keyboard control, by pressing the arrow keys to control the movement of turtle1, and then turtle2 will chase turtle1 to move.

10.2.7 Python language implements tf broadcaster

1. In the function package learning_tf, create a folder script, switch to this directory, and create a new .py file named turtle_tf_broadcaster.py
2. copy and paste the program code below into the turtle_tf_broadcaster.py file

```
#!/usr/bin/env python
# -*- coding: utf-8 -*-

import roslib
roslib.load_manifest('learning_tf')
import rospy

import tf
import turtlesim.msg

def handle_turtle_pose(msg, turtlename):
    br = tf.TransformBroadcaster() #define a tf broadcast
    # Broadcast tf transformation between world and input named turtle
    br.sendTransform((msg.x, msg.y, 0)
                    tf.transformations.quaternion_from_euler(0, 0, msg.theta)
                    rospy.Time.now()
                    turtlename,
                    "world")

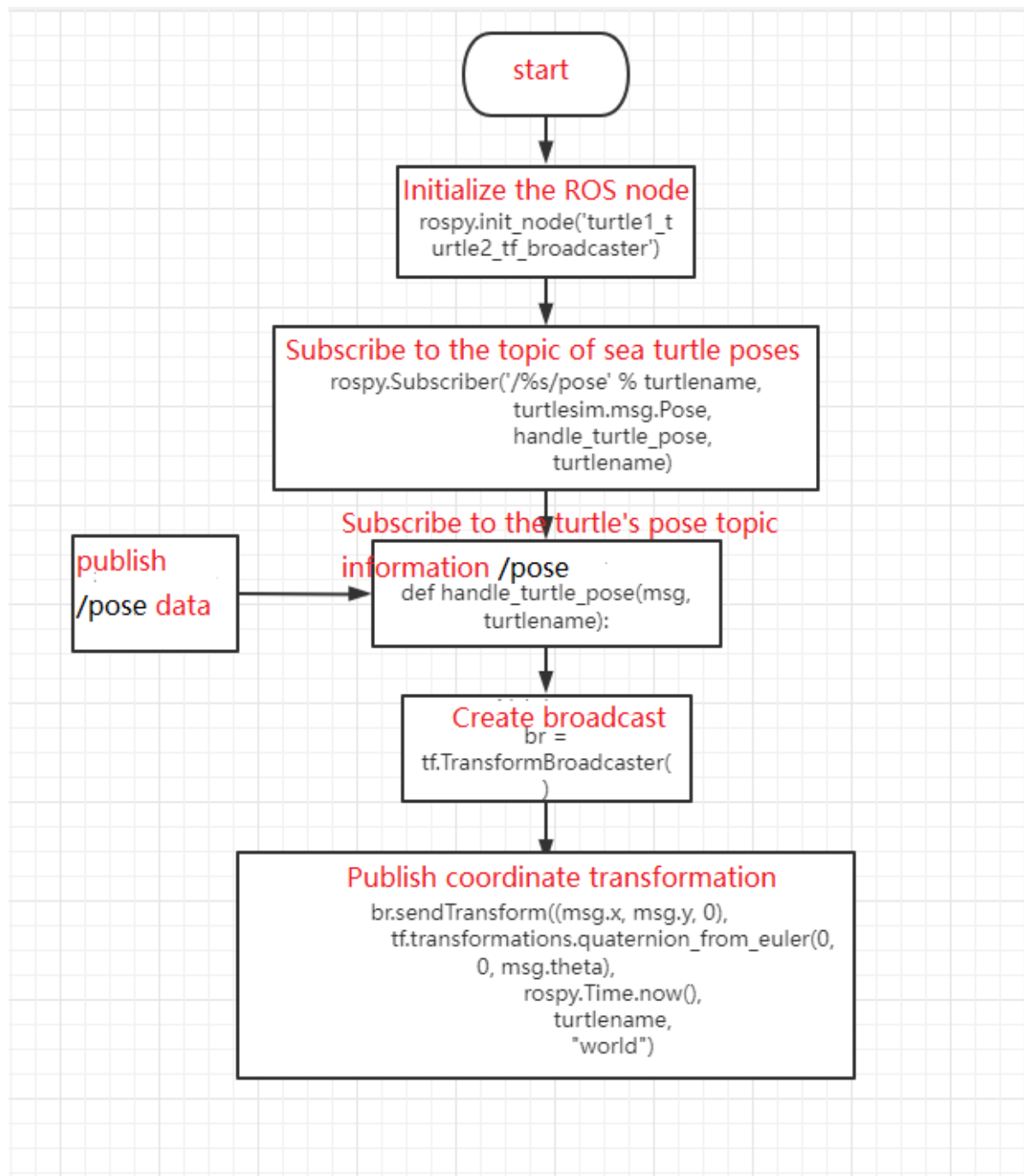
if __name__ == '__main__':

    rospy.init_node('turtle1_turtle2_tf_broadcaster') ros node

    turtlename = rospy.get_param('~turtle') the turtle's name from the parameter
server
    #Subscribe/pose topic data, which is turtle's pose information
    rospy.Subscriber('/%s/pose' % turtlename,
                    turtlesim.msg.Pose,
                    handle_turtle_pose,
                    turtlename)

    rospy.spin()
```

3. program flow chart



10.2.8 Python language implements tf listener

1. In the script folder of the function package `learning_tf`, create a python file(the file suffix is .py) and name it `turtle_tf_listener.py`
2. copy and paste the program code below into the `turtle_tf_listener.py` file

```

# !/usr/bin/env python
# -*- coding: utf-8 -*-

import rospy
import math
import tf
import geometry_msgs.msg
import turtlesim.srv

if __name__ == '__main__':
    rospy.init_node ' #Initialize(turtle_tf_listener)' ros node

```

```

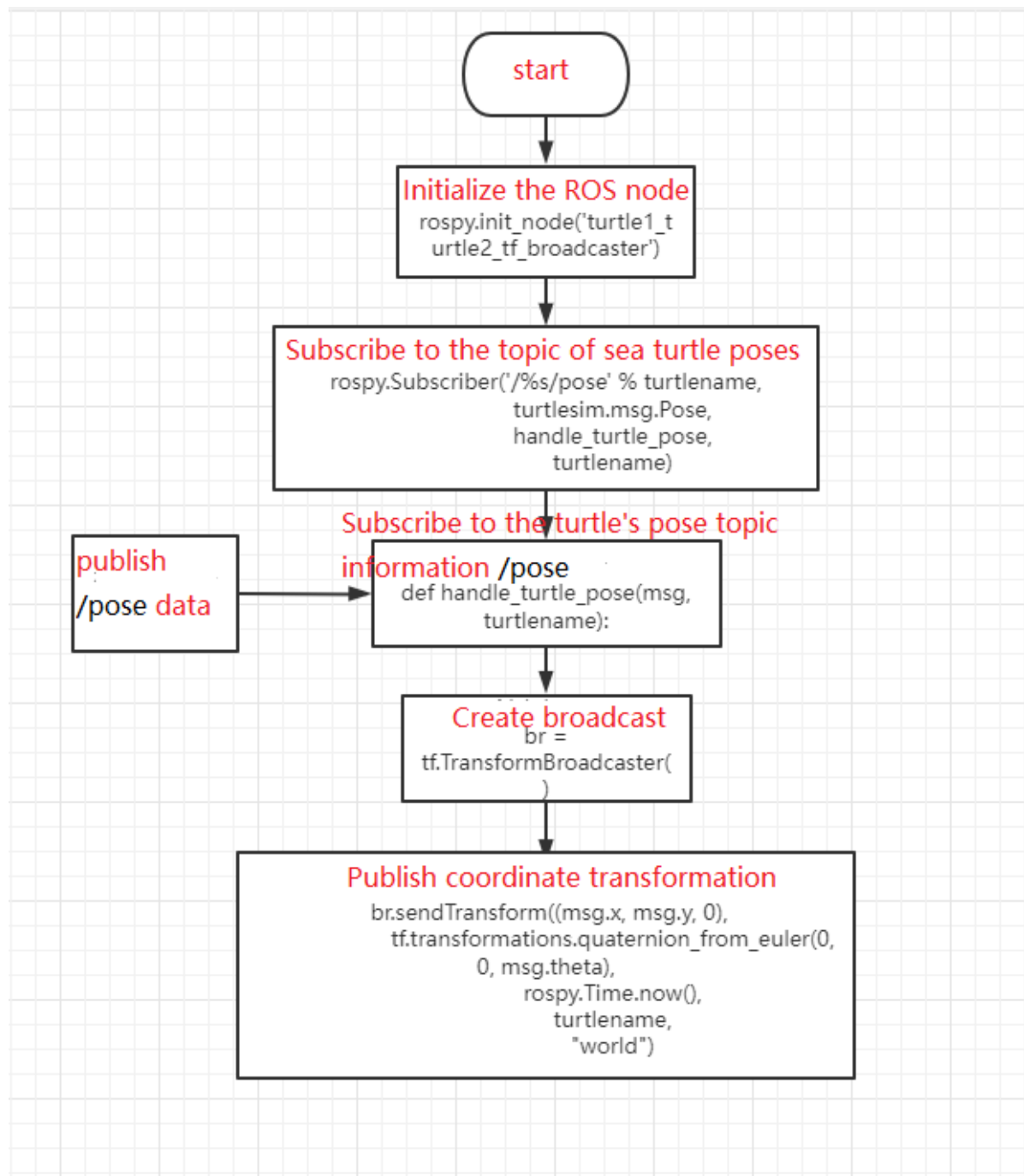
listener = tf.TransformListener() #Initialize a listener

rospy.wait_for_service('spawn')
#Call the service to spawn another turtle turtle2
spawner = rospy.ServiceProxy('spawn', turtlesim.srv.Spawn)
spawner(8, 6, 0, 'turtle2')
#declare a publisher to publish the speed of turtle2
turtle_vel = rospy.Publisher('turtle2/cmd_vel', geometry_msgs.msg.Twist,
queue_size = 1)

rate = rospy.Rate(10.0)
while not rospy.is_shutdown():
    try :
        #Find tf changes between turtle2 and turtle1
        (trans, rot) = listener.lookupTransform('/turtle2', '/turtle1',
rospy.Time(0))
    except (tf.LookupException, tf.ConnectivityException,
tf.ExtrapolationException):
        continue
    #Through mathematical calculation, calculate the linear velocity and
angular velocity, and then publish it
    angular = 6.0 * math.atan2(trans [ 1 ], trans [ 0 ])
    linear = 0.8 * math.sqrt(trans [ 0 ] ** 2 + trans [ 1 ] ** 2)
    cmd = geometry_msgs.msg.Twist()
    cmd.linear.x = linear
    cmd.angular.z = angular
    turtle_vel.publish(cmd)
    rate.sleep()

```

3. program flow chart



10.2.9 Display of startup and running effects

1. write a launch file

In the function package directory, create a new folder launch, switch to launch, create a new launch file, name it start_tf_demo_py.launch, and copy the following content into it,

```
< launch >

<!-- Turtle Node-->
< node pkg = "turtlesim" type = "turtlesim_node" name = "sim" />
<!--Broadcast turtle1->world-->
< node name = "turtle1_tf_broadcaster" pkg = "learning_tf" type =
"turtle_tf_broadcaster.py" respawn = "false" output = "screen" >
  < param name = "turtle" type = "string" value = "turtle1" />
</ node >
<!--broadcast turtle2->world-->
< node name = "turtle2_tf_broadcaster" pkg = "learning_tf" type =
"turtle_tf_broadcaster.py" respawn = "false" output = "screen" >
```

```

    < param name = "turtle" type = "string" value = "turtle2" />
  </ node >
  <!--Monitor-->
  < node pkg = "learning_tf" type = "turtle_tf_listener.py" name =
"listener" />
  <!--Turtle keyboard control node-->
  < node pkg = "turtlesim" type = "turtle_teleop_key" name = "teleop"
output = "screen" />
</ launch >

```

2. start

```
roslaunch learning_tf start_tf_demo_py.launch
```

After the program runs, click the mouse on the window to run launch, press the arrow keys, turtle2 will move with turtle1.

3. the operation result is as follows

