



Hochschule  
**Bonn-Rhein-Sieg**  
University of Applied Sciences

**b-it** Bonn-Aachen  
International Center for  
Information Technology

# Introduction to ROS

## Foundation Course

August 25, 2019

Hassan Umari

## 1. What is ROS?

1.1 What ROS is

1.2 What ROS is NOT

## 2. Analogy Between ROS and Operating Systems

## 3. Features of ROS

3.1 Language independent

3.2 Distributed and Modular

3.3 A lot of libraries and tools

3.4 Bad Things About ROS

## 4. ROS Concepts

4.1 File system level

4.2 Computation graph level

4.3 Community level

## 5. References



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# What ROS is

*Robot Operating System*

- Short for: Robot Operating System.
- A collection of libraries and tools.
- It helps software developers create robot applications.



How Robotics  
Research Keeps...

# Re-Inventing the Wheel

First, someone publishes...



...and they write code that barely works but lets them publish...



...a paper with a proof-of-concept robot.



This prompts another lab to try to build on this result...



But inevitably, time runs out...



...and countless sleepless nights are spent writing code from scratch.



So, a grandiose plan is formed to write a new software API...



...and all the code used by previous lab members is a mess.

# What ROS is

*Robot Operating System*

- A way to standardize writing software for robots.
- It enhances **code reusability** .

- ROS is open-source .
- It is a meta-operating system.
- ROS can be installed on Ubuntu and Debian (so it's currently supported on Linux only).



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# What ROS is NOT

*Robot Operating System*

- It is NOT a programming language.
- It is NOT an integrated development environment (IDE).
- It is NOT a stand-alone operating system



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# Analogy Between ROS and Operating Systems



Software Applications

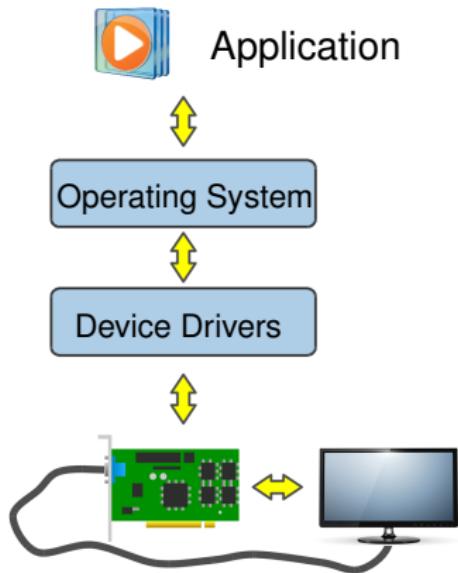
work on



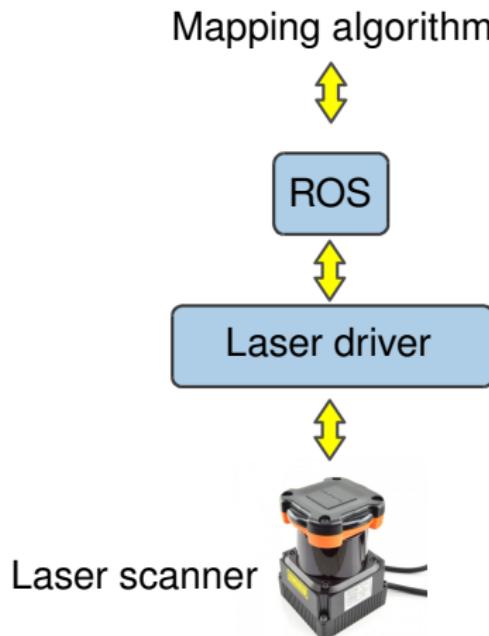
Different hardware



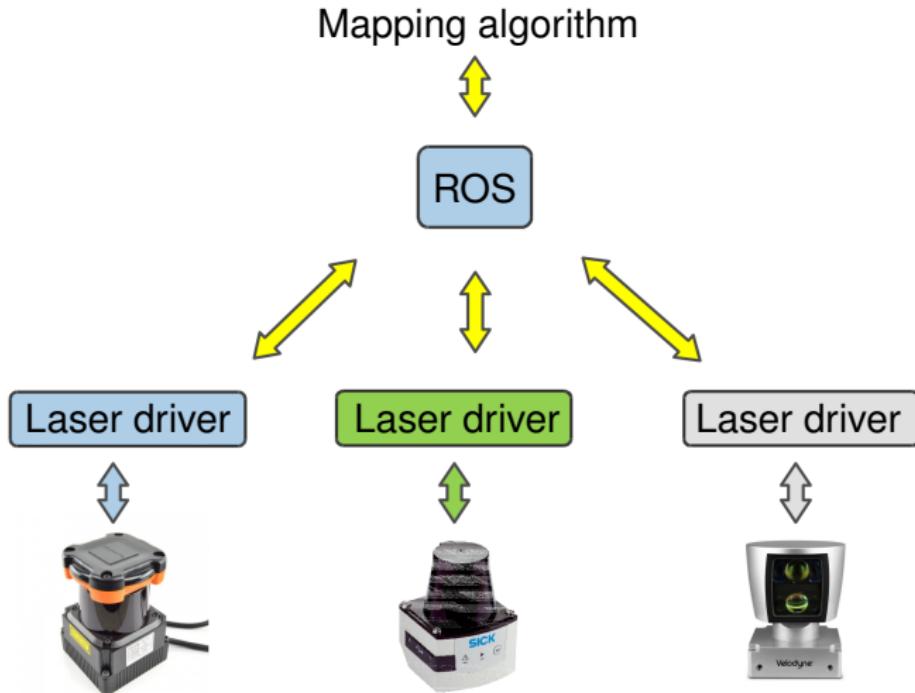
# Analogy Between ROS and Operating Systems



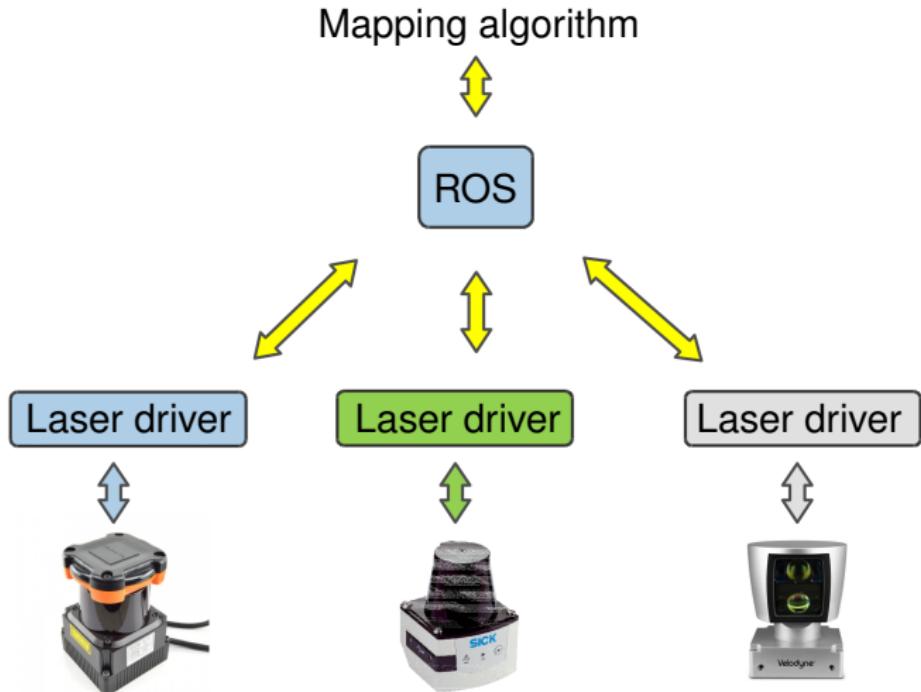
# Analogy Between ROS and Operating Systems



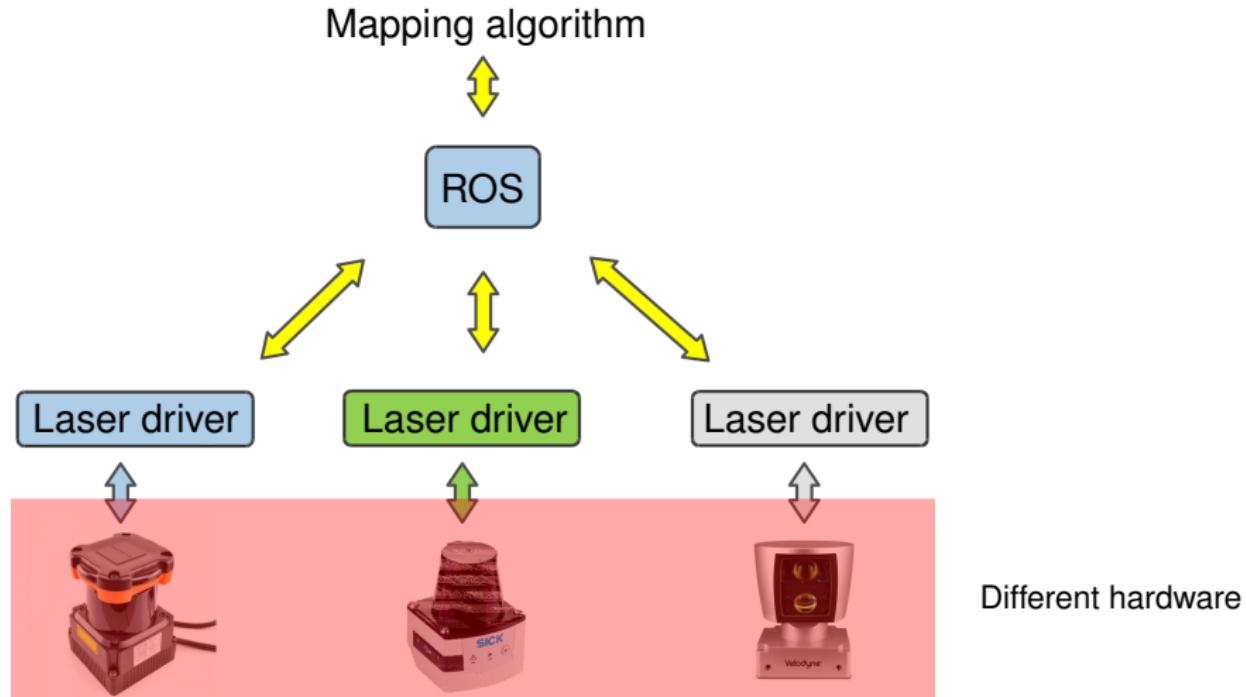
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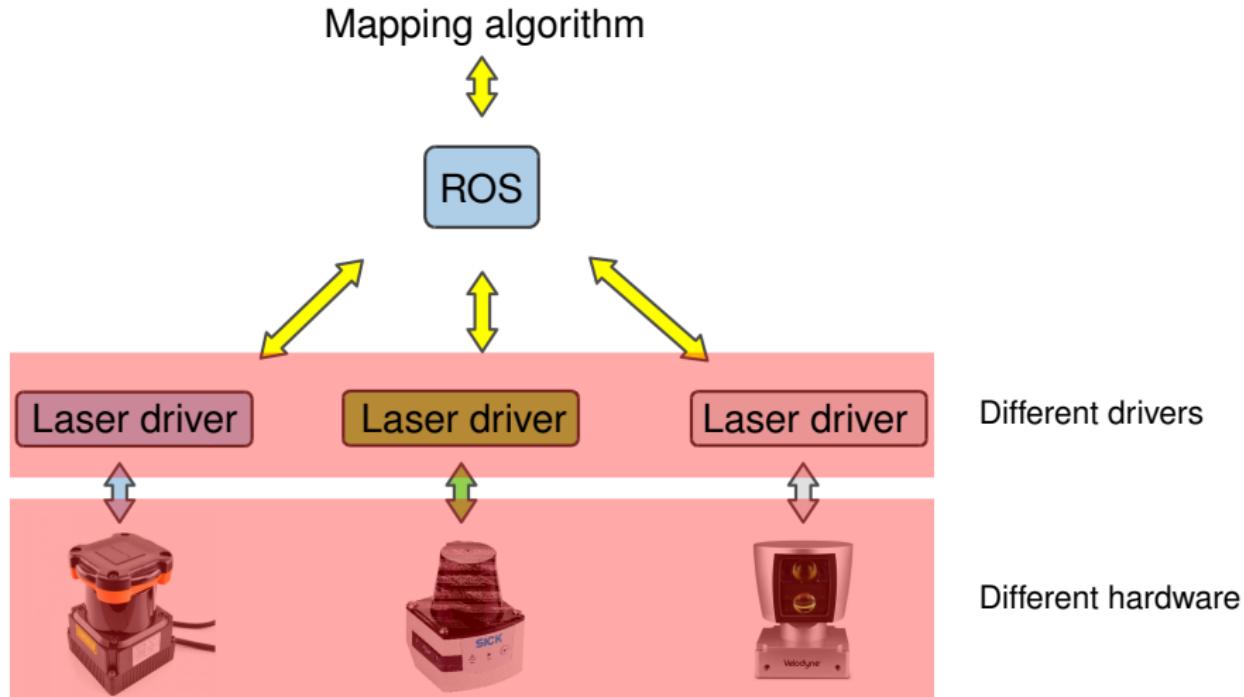
# Analogy Between ROS and Operating Systems



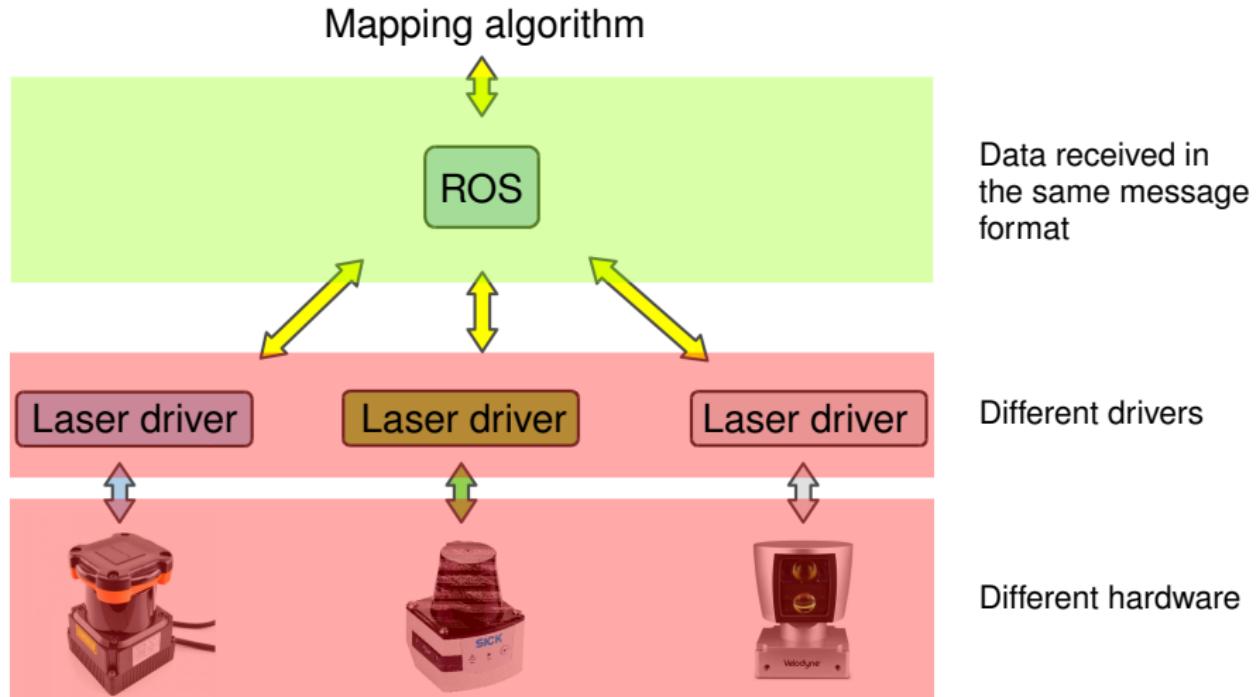
# Analogy Between ROS and Operating Systems



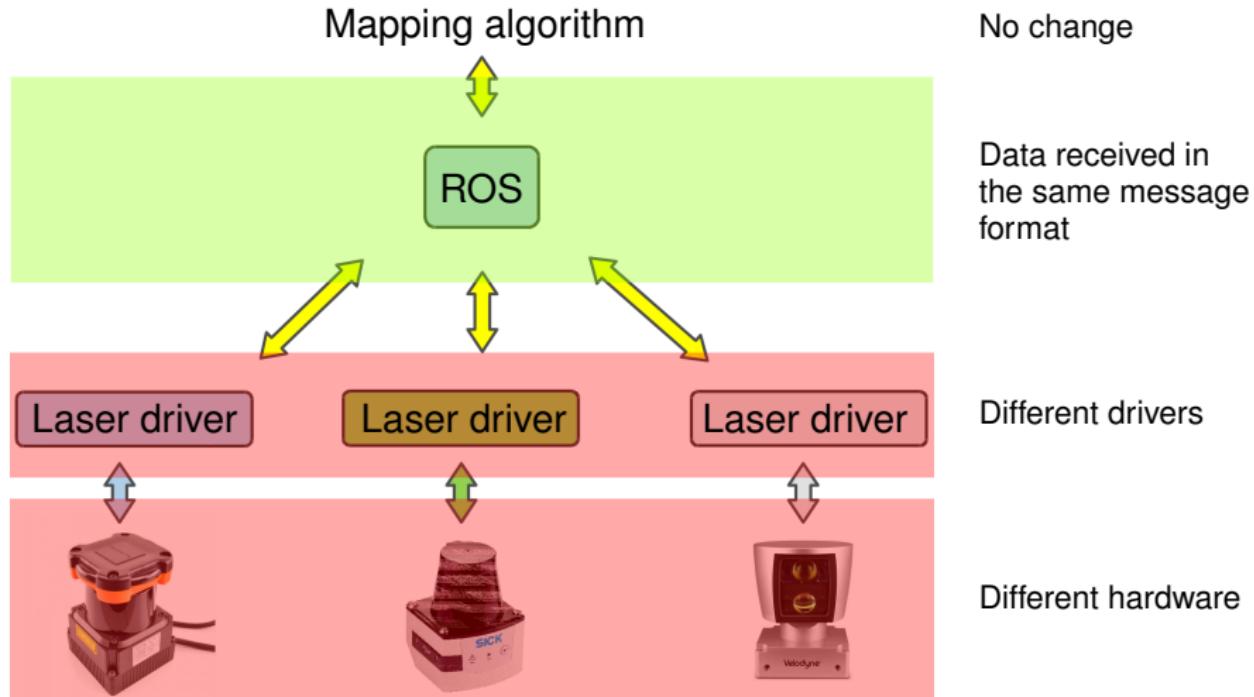
# Analogy Between ROS and Operating Systems



# Analogy Between ROS and Operating Systems



# Analogy Between ROS and Operating Systems



# Analogy Between ROS and Operating Systems

Mapping      Navigation      pick & place

Robot Applications

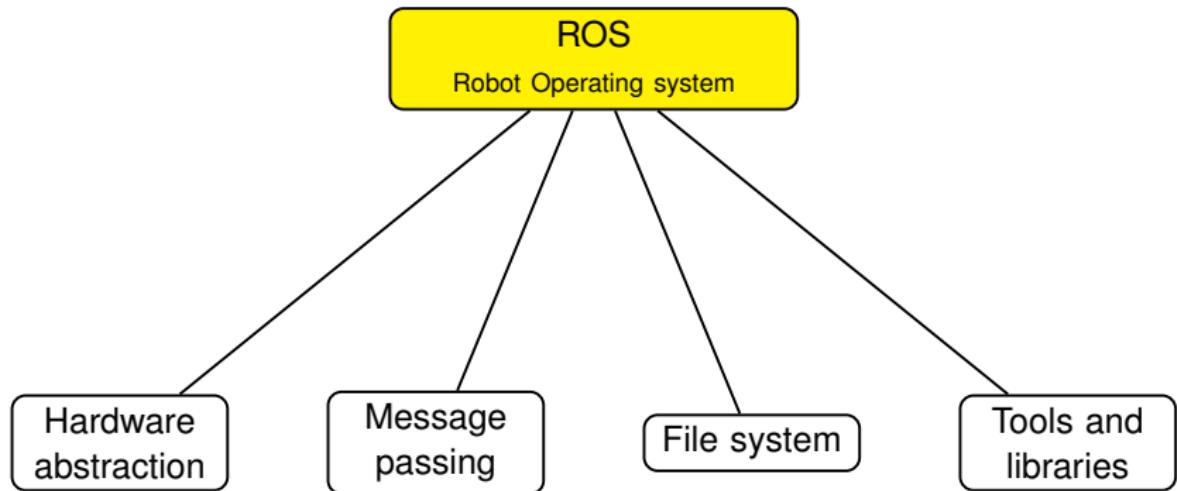
work on



Different hardware



# Analogy Between ROS and Operating Systems



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# Features of ROS

- Language independent.
- Distributed and Modular.
- A lot of libraries and tools.
- Open Source.
- Active Community.



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- 4.1 File system level
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# Features of ROS

*Language independent*

- ROS functionalities are implemented as a library in different programming languages.
- These libraries are referred to as ROS client libraries.



# Language independent

## Features of ROS

ROS client libraries.

- Main ROS Client libraries:
  - roscpp
  - rospy
  - roslib
- Experimental ROS client libraries:
  - rosjava
  - rosruby
  - and some others..
- ROS support on MATLAB:
  - Robotics System Toolbox



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# Distributed and Modular

## *Features of ROS*

- ROS supports running processes on multiple computers connected together through a LAN.
- In a system running ROS, there will be multiple of processes where each process can do certain task. A process can be changed without altering the remaining processes.



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# A lot of libraries and tools

## *Features of ROS*

- Examples of libraries:
  - Navigation stack.
  - SLAM (gmapping, hector SLAM, etc..).
  - Localization (amcl, etc..).
  - Motion planning for manipulators (MoveIt)
  - Support for popular libraries (OpenCV, PCL).
- Examples of tools:
  - RVIZ:3D Visualization.
  - ROS bag files: Logging Sensor Data.
  - Catkin: A Build System.
  - Command line tools.



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# Bad Things About ROS

- Learning ROS needs time.
- It needs a computer. Does not work on a microcontroller!
- Not optimized for multiple robots.
- Supported only on Linux, no support for Windows or macOS.



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- 4.2 Computation graph level
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## 5. References



# ROS Concepts

## ROS concepts

- File system level
- Computation graph level
- Community level



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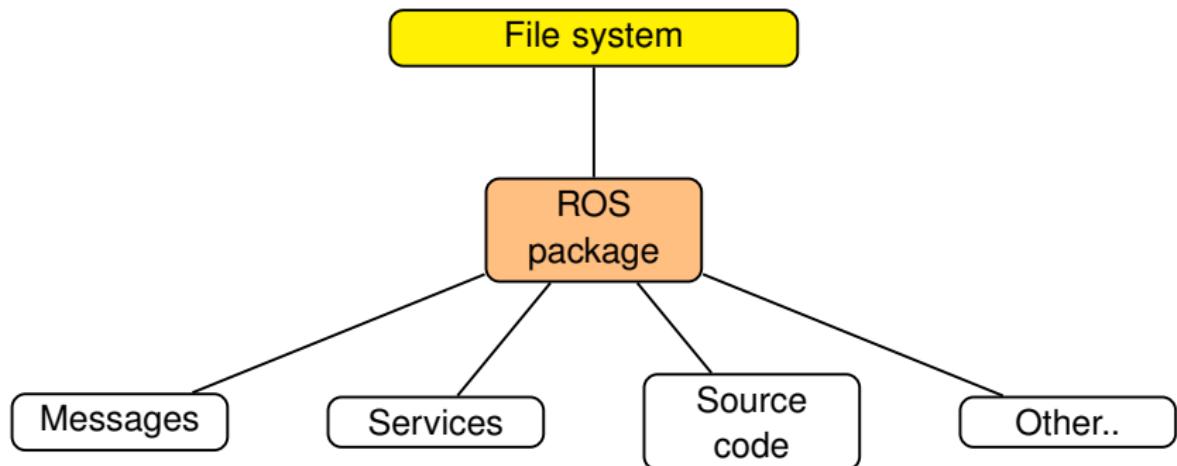
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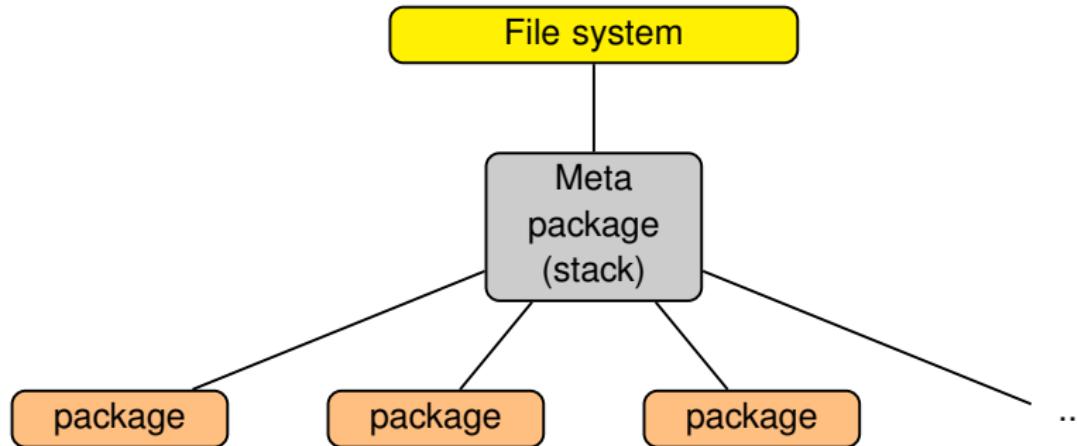
# File system level

## ROS Concepts



# File system level

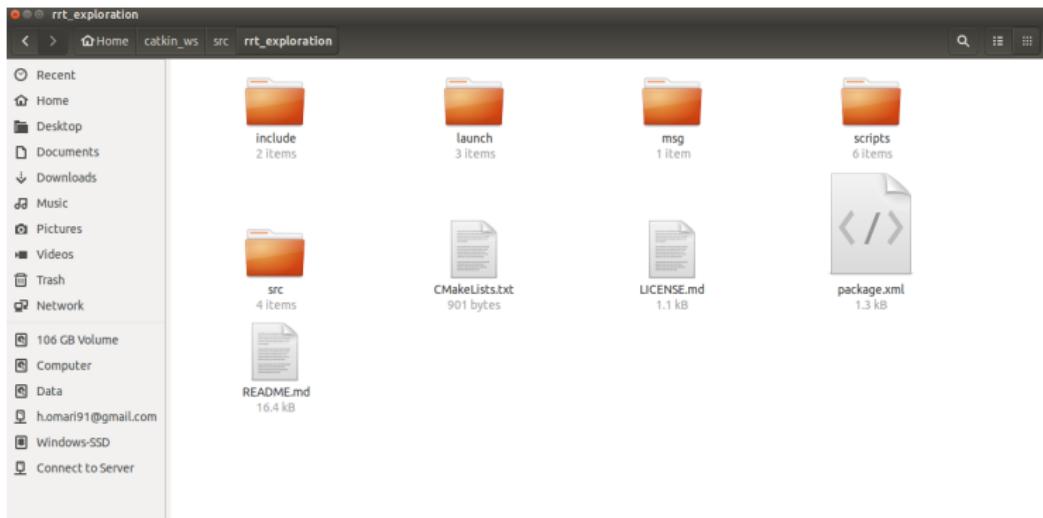
## ROS Concepts



# File system level

## *ROS Concepts*

Inside a ROS package:



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# Computation graph level

## *ROS Concepts*

- In an application that uses ROS, the computations are executed by a collection of processes called Nodes.
- Nodes are connected together in a peer-to-peer network.
- This network of nodes do all the computation and is referred to as ROS computation graph.
- ROS Nodes can be run on single or multiple computers.



# Computation graph level

## *ROS Concepts*

Concepts related to ROS computation graph:

1. Nodes.
2. Topics.
3. Messages.
4. Master.
5. Services.
6. Actions
7. Parameter Server.
8. Bags.



# Computation graph level

## *ROS Concepts*

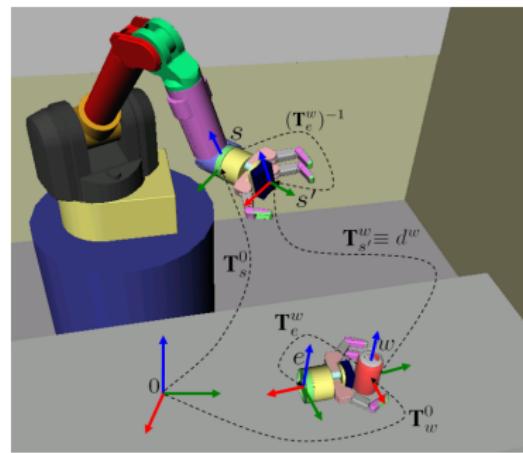
### Nodes:

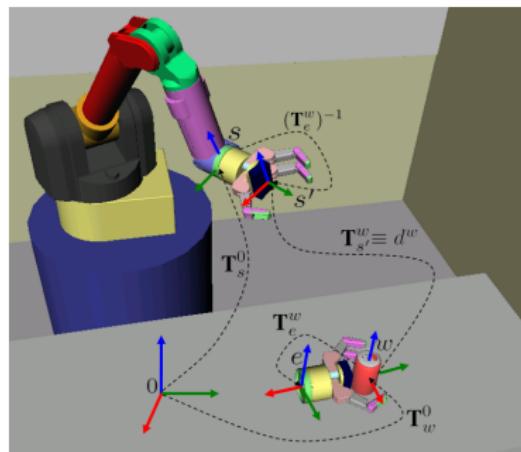
- A ROS node is a process that exchanges data with other processes through ROS network.
- It may be a python script, a C++ written process, or even a MATLAB script.
- Nodes perform computation.

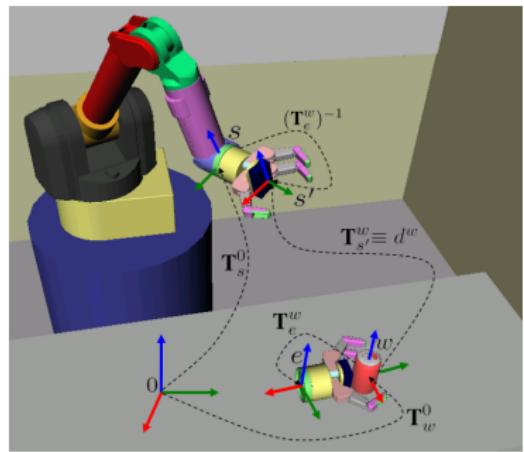
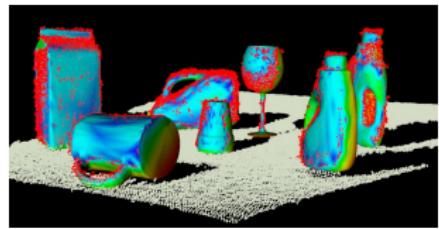






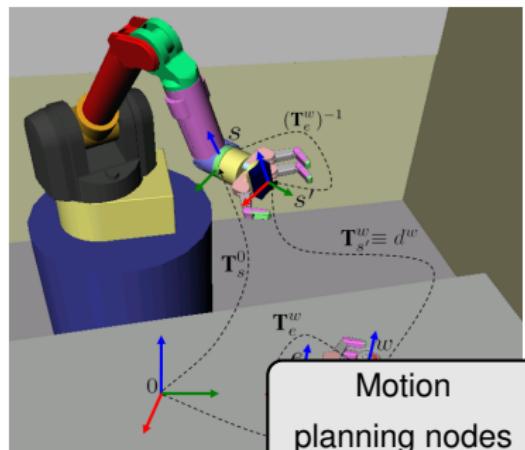
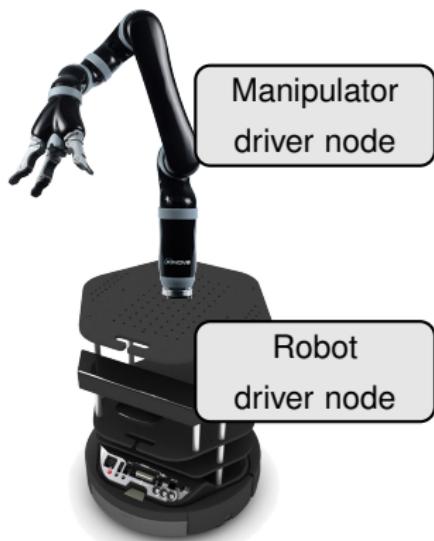
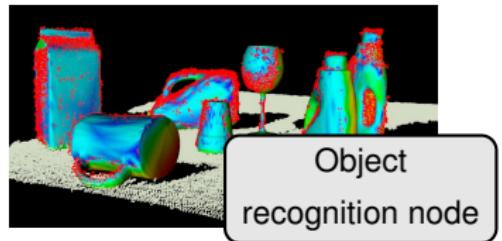
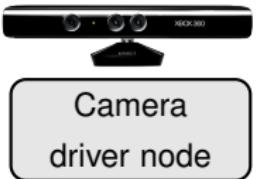








ROS master  
node



# Computation graph level

*ROS Concepts*

## Topics and Messages:

- Nodes send data by publishing messages on a named topic.
- Nodes receive data by subscribing to a topic.
- Multiple nodes can publish/subscribe to the same topic.



# Computation graph level

*ROS Concepts*

## Topics and Messages:

- Publisher node publishes the messages on a topic at a chosen frequency.
- This **publish/subscribe** communication paradigm is a many-to-many one-way transport mechanism of data.
- The publishing node and subscribing node are not aware of each other's existence.



# Computation graph level

## *ROS Concepts*

### Master:

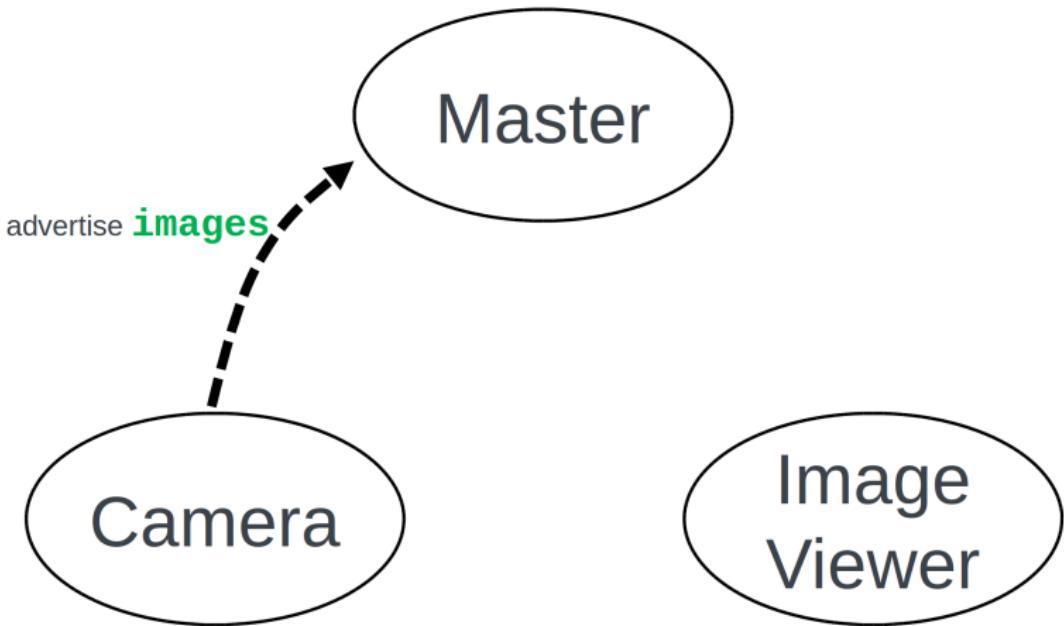
- The first process to run in an application that uses ROS, is the Master.
- The ROS Master provides name registration and lookup to the rest of the nodes.
- In a distributed system, we should run the master on one computer, and other remote nodes can find each other by communicating with this master.

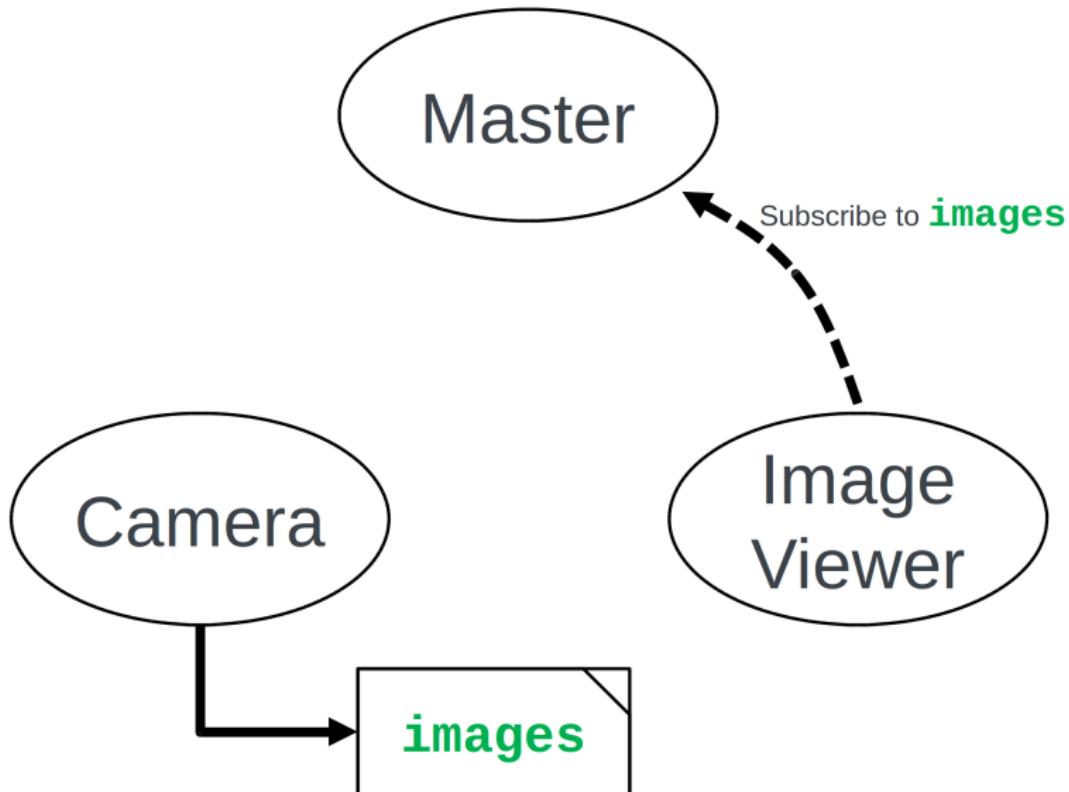


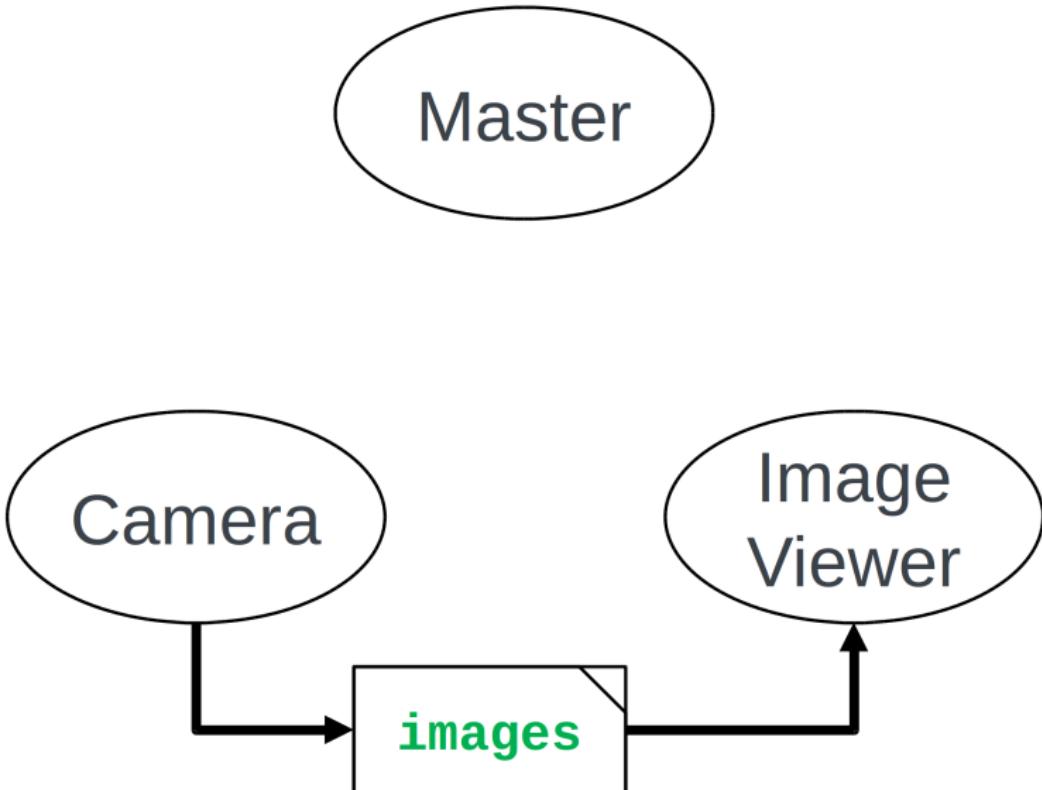
Master

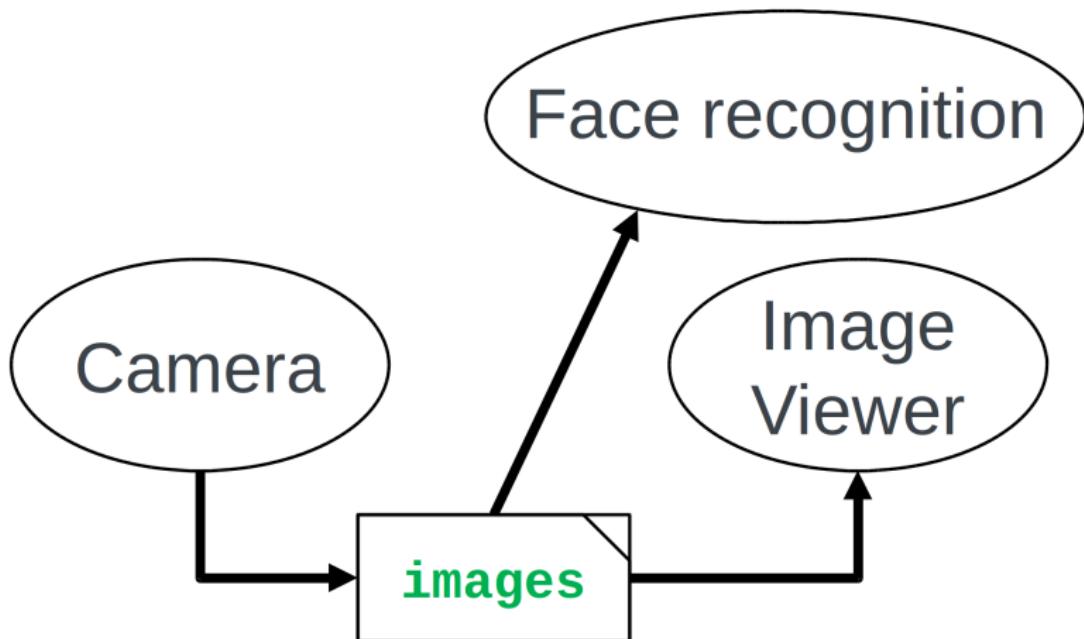
Camera

Image  
Viewer







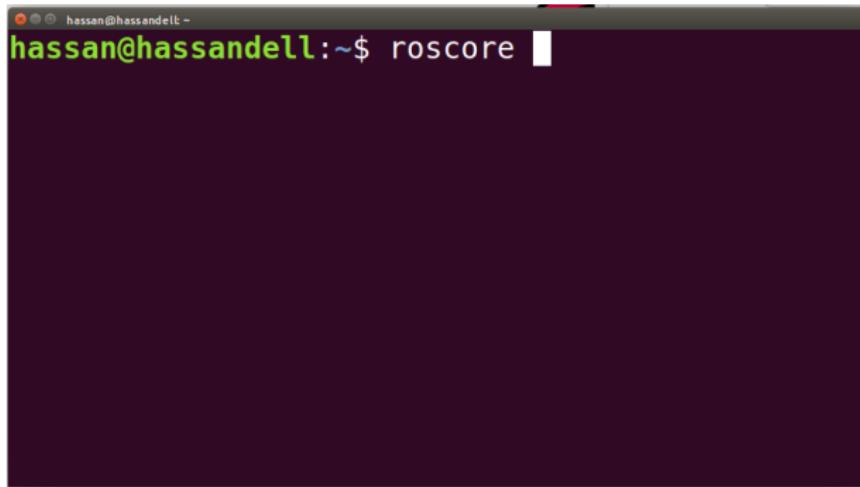


# Computation graph level

*ROS Concepts*

## Master:

- ROS master is invoked by this command:



A screenshot of a terminal window on a dark background. The window title bar shows three small icons. The terminal prompt is "hassan@hassandell:~\$". Below the prompt, the command "roscore" is typed and followed by a red cursor character. The rest of the terminal window is blank.

```
hassan@hassandell:~$ roscore
```



# Example (TurtleSim)

# Computation graph level

## *ROS Concepts*

Concepts related to ROS computation graph:

1. Nodes.
2. Topics.
3. Messages.
4. Master.
5. Services.
6. Actions
7. Parameter Server.
8. Bags.



# Computation graph level

## *ROS Concepts*

### Services:

- In many scenarios a publish/subscribe model is not enough, it's a one-way communication.
- Example scenario: plan a path service.
- ROS Services provide an additional way of communication between nodes, a **request / reply** interaction.



# Computation graph level

## *ROS Concepts*

### Services:

- It happens between two nodes, the service **server** node, and the service **client** node.
- A Client node sends a request for a named service and waits for the response, a node serving this service responds, and the communication is over.
- it is a one-to-one, two-way, one-time communication.

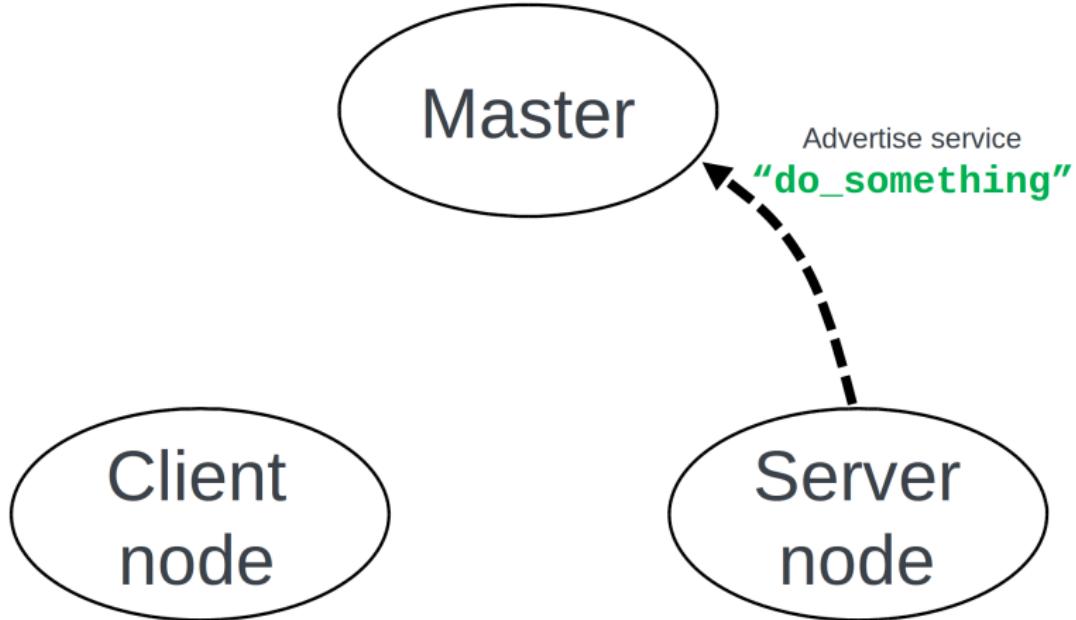


```
graph TD; Master((Master)); Client((Client node)); Server((Server node));
```

Master

Client  
node

Server  
node

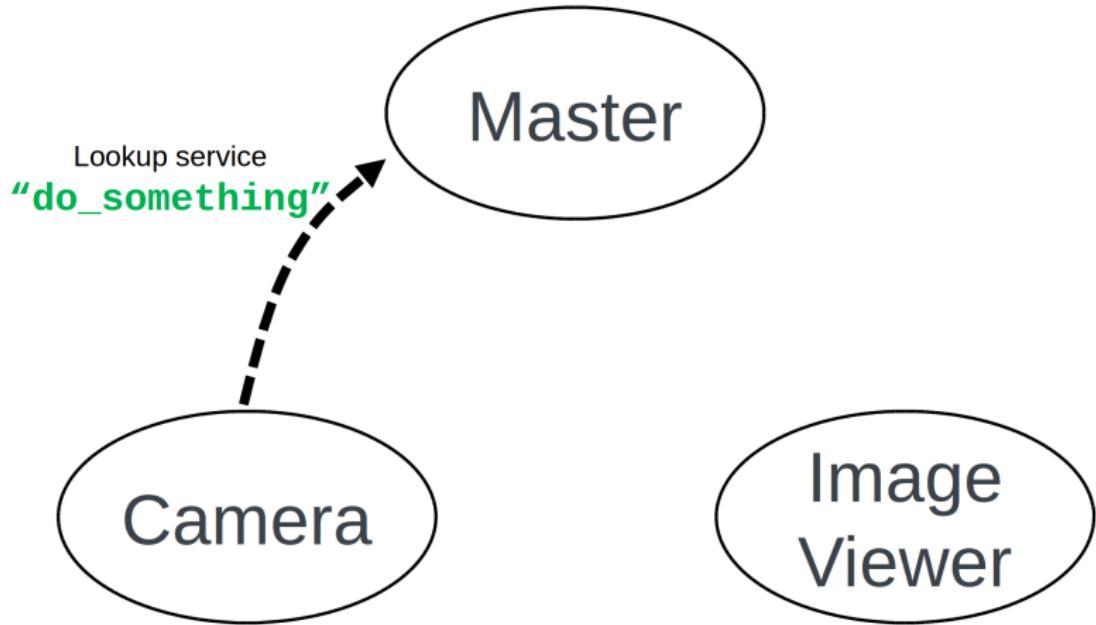


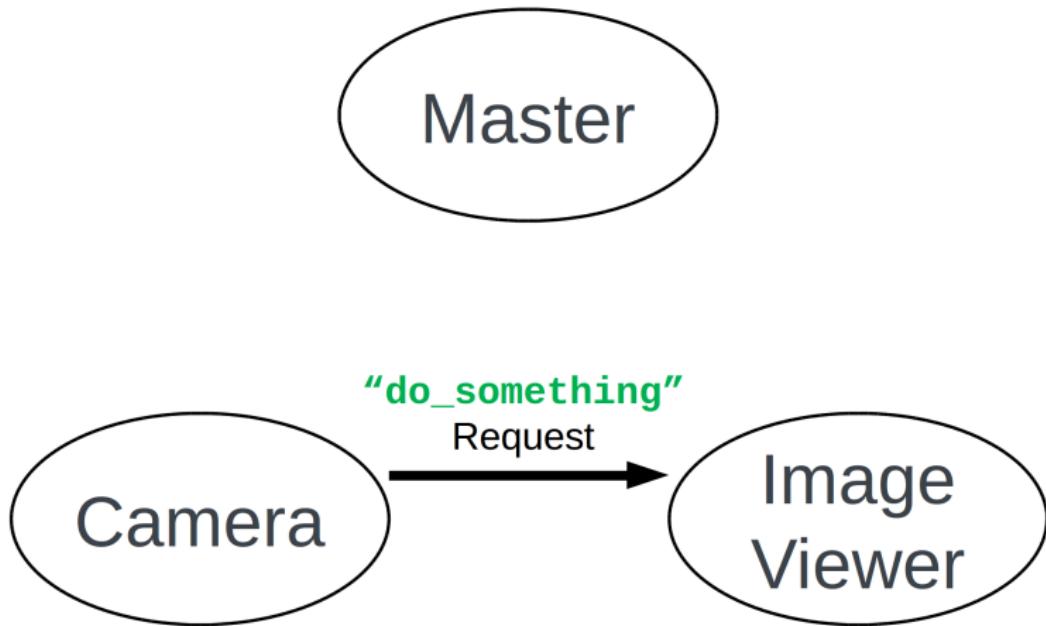
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```

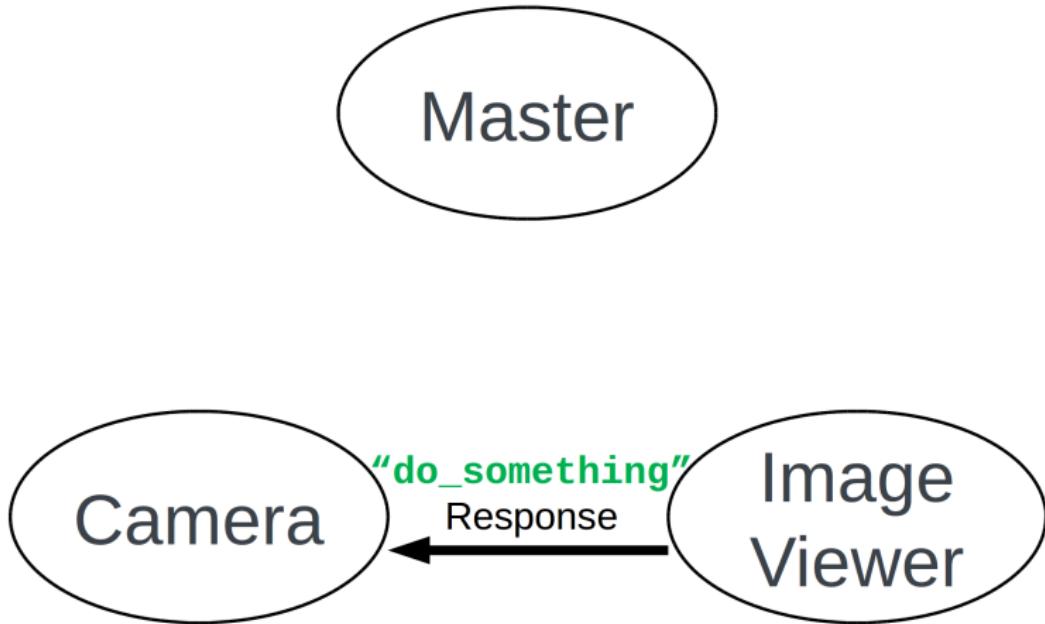
Master

Client  
node

Server  
node







```
graph TD; Master((Master)); Client((Client node)); Server((Server node));
```

Master

Client  
node

Server  
node

Example  
(TurtleSim again)

# Computation graph level

## *ROS Concepts*

### Actions:

- ROS services are not suitable for long-term tasks, a client that have sent a service request keeps on waiting for the response from the server. ROS actions solves this.
- In ROS actions, an action client sends a request to the server, the client doesn't have to wait for the response.



# Computation graph level

*ROS Concepts*

## Actions:

- Action client can request for feedback which the action server provides during execution.
- Once the server finishes executing the task, it send a result message to the client.



# Computation graph level

*ROS Concepts*

## Parameter Server:

- A network-shared dictionary accessible to all nodes.
- Typically used to store static data, like parameters and configurations.
- A central location to store static values.
- All nodes can access and modify those values.
- Parameter server is a part of ROS Master.



# Computation graph level

*ROS Concepts*

## Bags:

- ROS bag is a mechanism for recording data for later playback.
- You can record a complete session, with all the topics and messages being exchanged along with their time stamping.



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## 5. References



# Community level

## *ROS Concepts*

Concepts related to ROS development process and it's community:

1. The ROS Wiki.
2. Repositories.
3. Mailing Lists.
4. ROS Answers.
5. ROS Distributions.



# Community level

*ROS Concepts*

## ROS Distributions:



ROS Melodic  
5.2018 - 5.2023  
(LTS)  
(Ubuntu 18 EOL)



ROS Lunar  
5.2017 - 4.2019



ROS Kinetic  
5.2016 - 4.2021  
(LTS)  
(Ubuntu 16 EOL)  
(what we use)



ROS Indigo  
7.2014 - 4.2019  
(LTS)  
(Ubuntu 14 EOL)



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# References

1. ROS Wiki.
2. ROS2 Wiki, on the drawbacks of ROS:

[http://design.ros2.org/articles/why\\_ros2.html](http://design.ros2.org/articles/why_ros2.html).

3. Overview on ROS services: <https://www.youtube.com/watch?v=qhnImrGQVvM>.
4. ROS introduction slides by Rada:

[https://wiki.ros.org/Events/CoTeSys-ROS-School?action=AttachFile&do=get&target=ros\\_tutorial.pdf](https://wiki.ros.org/Events/CoTeSys-ROS-School?action=AttachFile&do=get&target=ros_tutorial.pdf).



Thank you

Any questions?