

Puzzlebot Emdial Guide

Usage and Installation Guide.

For **v1.2.2 Release**. June 14, 2025

Developed by *Team Emdial*.

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v1.2.2 Release Contents

The ***puzzlebot_emdial repository*** contains all packages developed for each Minichallenge, final challenge and extra tools. The repository is structured as follows:

Where the Final Challenge package is named ***puzzlebot_emdial*** inside the ***src*** folder.

```
puzzlebot_emdial/
└── src/
    ├── mc1_opencontrol/
    ├── mc2_motioncontrol/
    ├── mcHT_traffic_light/
    ├── line_follower/
    ├── puzzlebot_emdial/
    ├── toolbox_pkg/
    ├── webcam_pub/
    ├── mobile_robotics/
    ├── puzzlebot_description/
    └── puzzlebot_gazebo/
```

```
└── train/  
└── data/  
└── models/  
└── extra/  
└── .gitignore  
└── manual_ejecucion.md  
└── README.md  
└── LICENSE  
└── requirements.txt  
└── mod1_requirements.txt  
└── modA_requirements.txt
```

Requirements for any package in the repository

To run any package in the *puzzlebot_emdial repository*, you need to have the following prerequisites:

1. **ROS2 Humble:** Ensure you have ROS2 Humble installed on your system. You can follow the official [Installation guide](#).
2. **Python 3.10:** The packages in this repository are compatible with Python 3.10. Make sure you have it installed. (other versions may work, but they are not tested)
3. **Ubuntu 22.04:** The packages are developed and tested on Ubuntu 22.04. While they may work on other versions, it is recommended to use Ubuntu 22.04 for compatibility. Any architecture is supported.

Local machine Installation

Installing the *puzzlebot_emdial package* from **Repo as WS**

To **Install** the *puzzlebot_emdial package*, follow these steps:

1. **Obtain the source files:**

- **Download Release (Recommended):**

Download the latest release from the [Releases page](#).

- Extract the downloaded archive to a directory of your choice. This will create a folder named *puzzlebot_emdial* containing ALL the source files.

- **OR clone the repository:**

If you prefer to clone the repository, you can do so with the following command:

```
git clone
```

Make sure to select the correct branch/tag for the latest version (see version in the [Title](#) of this document).

2. Navigate to the Repository/Workspace directory:

```
cd puzzlebot_emdial/
```

3. Install dependencies:

Make sure you have the required Python dependencies installed. You can use the provided `modA_requirements.txt` files:

```
pip install -r ../../modA_requirements.txt
```

Why `modA_requirements.txt`?

The `modA_requirements.txt` file contains the necessary dependencies without extra noise created by the `pip freeze` command within a ROS2 environment. In other words, its a version of the `requirements.txt` file thats ready to run with pip install to avoid errors.

If you are still encountering errors **or want to avoid any potential issues with your ROS2 installation**, try to manually install the dependencies listed in the `requirements.txt` file.

4. Source the ROS2 environment:

Make sure to source your ROS2 environment. If you are using a standard ROS2 installation, you can do this with:

```
source /opt/ros/humble/setup.bash
```

5. Build the workspace:

If you are using a workspace, build it with:

```
colcon build
```

Or specifically for the `puzzlebot_emdial package`:

```
colcon build --packages-select puzzlebot_emdial
```

6. Source the workspace:

After building, source the workspace to make the packages available:

```
source install/setup.bash
```

Installing the *puzzlebot_emdial package* as a Package in an **existing WS**

If you already have a suitable ROS2 workspace and want to add the *puzzlebot_emdial package* to it, follow these steps:

1. Navigate to your existing workspace:

```
cd /path/to/your/existing/workspace/
```

2. Clone/Paste the *puzzlebot_emdial package*:

- If you downloaded the release or cloned the repository, copy the *puzzlebot_emdial package* folder (inside `src`) to your existing workspace's `src` directory.

3. Follow steps 3 to 6 from the previous section ([Installing the *puzzlebot_emdial package* from Repo as WS](#)) to install dependencies, build the workspace, and source it.

Puzzlebot Installation

To run the Final Challenge package, it also needs to exist within the `src` folder of a ros2 workspace within the Puzzlebot.

Installing the *puzzlebot_emdial package* in the Puzzlebot

1. Remotely connect to the Puzzlebot:

Use SSH or any other remote connection method to access the Puzzlebot directories.

2. Navigate to the Puzzlebot's ROS2 workspace Directory:

The usual path for the Puzzlebot's ROS2 workspace `src` folder is:

```
cd /home/ros2_ws/src/
```

3. Paste the *puzzlebot_emdial package*:

Copy the *puzzlebot_emdial package* folder (inside `src`) to the Puzzlebot's ROs2 workspace's `src` directory.

4. Install dependencies:

Installation and running on the Puzzlebot should work with the native Python 3.10 ROS2 environment preinstalled on the Puzzlebot (when flashing the image).

5. Build the workspace:

If you are using a workspace, build it with:

```
colcon build
```

Or specifically for the *puzzlebot_emdial package*:

```
colcon build --packages-select puzzlebot_emdial
```

6. Source the workspace:

After building, source the workspace to make the packages available:

```
source install/setup.bash
```

Executing the *puzzlebot_emdial package*

Prior to executing any of the launch modes, make sure you have sourced the workspace where the *puzzlebot_emdial package* is installed. This can be done by running the following when inside your workspace directory:

```
source /install/setup.bash
```

Important: In ANY mode, it is **NECESSARY** to activate the System with a live parameter change. Its **HIGHLY RECOMMENDED** to use *rqt_reconfigure*:

```
ros2 run rqt_reconfigure rqt_reconfigure
```

This tool allows the user to change the *ctrl_activate* parameter to *true* in the *robot_ctrl* node, which is necessary for the Puzzlebot to start moving.

If you do not use *rqt_reconfigure*, you can also change the parameter manually using the following command (not tested):

```
ros2 param set /robot_ctrl ctrl_activate true
```

Also, many parameters can be changed for all nodes in the package using *rqt_reconfigure* to play around and test different configurations, the base configurations are preserved in the *config* folder of the package and loaded each time when the package is launched.

Launching in ONBOARD MODE (Recommended)

Running some nodes onboard the Puzzlebot and others on a local machine is the recommended way to run the [puzzlebot_emdial package](#).

The launch files can be run in **any order**, but it is recommended to run the Puzzlebot Launch first, and then the local machine Launch.

Launching Nodes for Local Machine

To run the package nodes that MUST run outside the Puzzlebot, use the following command:

```
ros2 launch puzzlebot_emdial emdial_loc_launch.py
```

Launching Nodes directly on the Puzzlebot

To run the package nodes that MUST run on the Puzzlebot, use the following command:

```
ros2 launch puzzlebot_emdial emdial_onb_launch.py
```

Launching in REMOTE MODE

Running all nodes on the local machine (remotely from the Puzzlebot) is not recommended, but it can be done if you want to test the package without the hassle of installing it on the Puzzlebot.

To run the package nodes remotely, use the following command:

```
ros2 launch puzzlebot_emdial emdial_rem_launch.py
```

Launching in SIMULATION MODE

Running the package in simulation mode is useful for testing and development purposes. Gazebo Sim Fortress or Garden is a requirement for this mode.

To run the [puzzlebot_emdial package](#) in simulation mode, use the following command:

```
ros2 launch puzzlebot_emdial emdial_sim_launch.py
```

For Simulation mode, you need to have the [puzzlebot_gazebo](#) package installed and sourced in your workspace as well as the [puzzlebot_description](#) package.

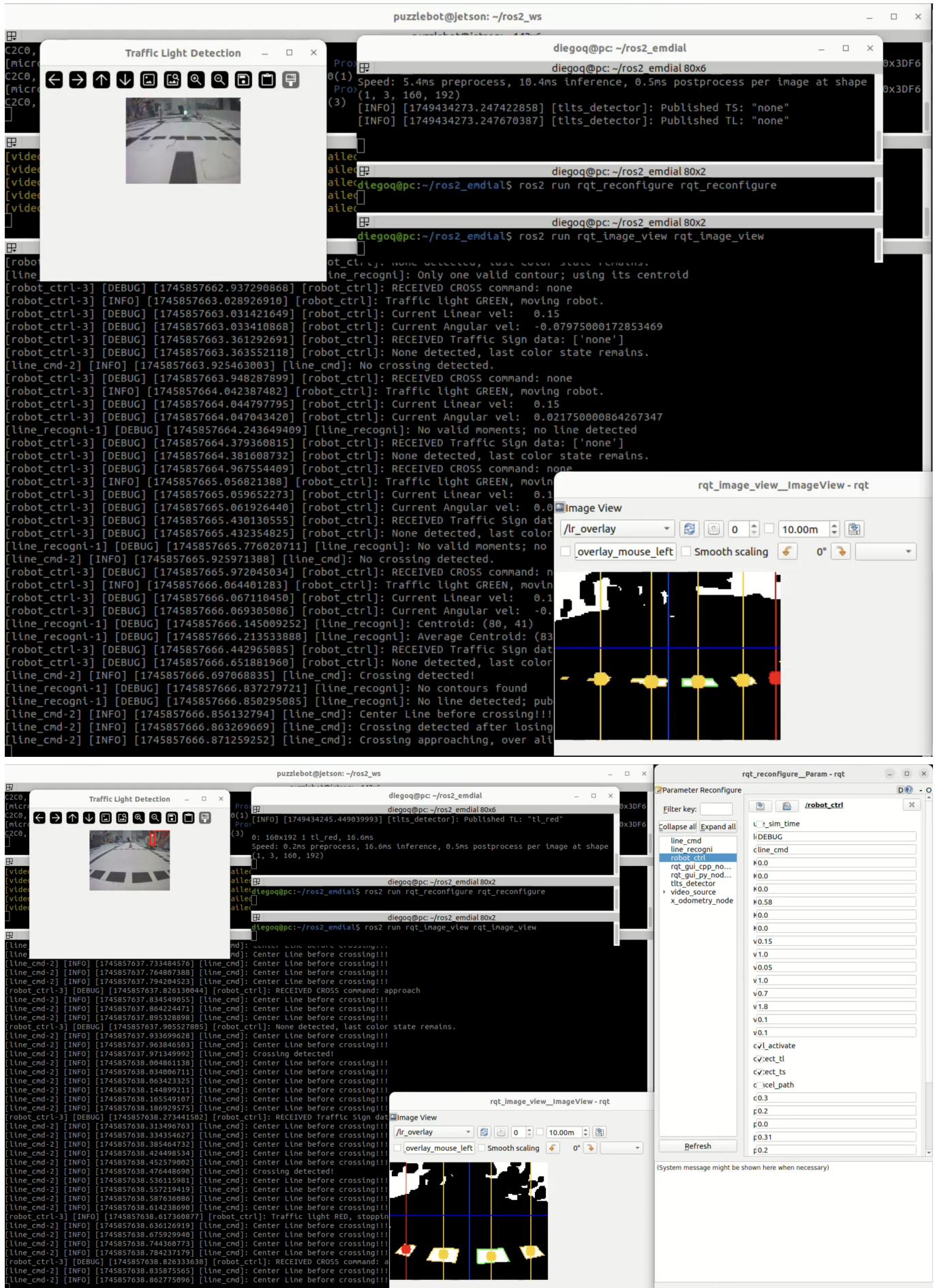
If all prerequisites are met, this command will launch the Gazebo simulation environment with the Puzzlebot model in a testing environment.

```
ros2 launch puzzlebot_gazebo gazebo_example_launch.py
```

Note: If you are running Ubuntu with a ARM64 architecture, make sure the `aldrick=` flag is set to `true` in the `gazebo_example_launch.py` file. This will ensure that the simulation runs correctly and accurately on arm64 machines.

Execution Examples (Screenshots)

Some examples of the package running in ONBOARD MODE.



Known Issues

See the [Issues page](#) on GitHub for known issues and troubleshooting.

Open an issue if you find a bug or have a feature request. The team will review it and respond as soon as possible.

License

This project is licensed under the MIT License. See the [LICENSE](#) file for details.

Acknowledgements

This project is developed by *Team Emdial* in solution of the *Puzzlebot Challenge* by *MCR2*.

Team Emdial, 2025

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