Simulation environment

When using ROS, we have the option of using both TCP/IP (TCPROS) or UDP (UDPROS) as our communication protocols. As stated in [1], the UDP protocol in ROS operates with low latency, which is an important aspect for our robotic arm. The TCP/IP protocol has more safety measures in terms of handshakes, thus making it slower. In addition, UDP is connectionless, which means that we don't need to establish a connection to communicate. Combined with the fact that the teacher recommended UDP, our chosen protocol is UDP.

Figure 1 shows a simple diagram of the communication between the components of the system.
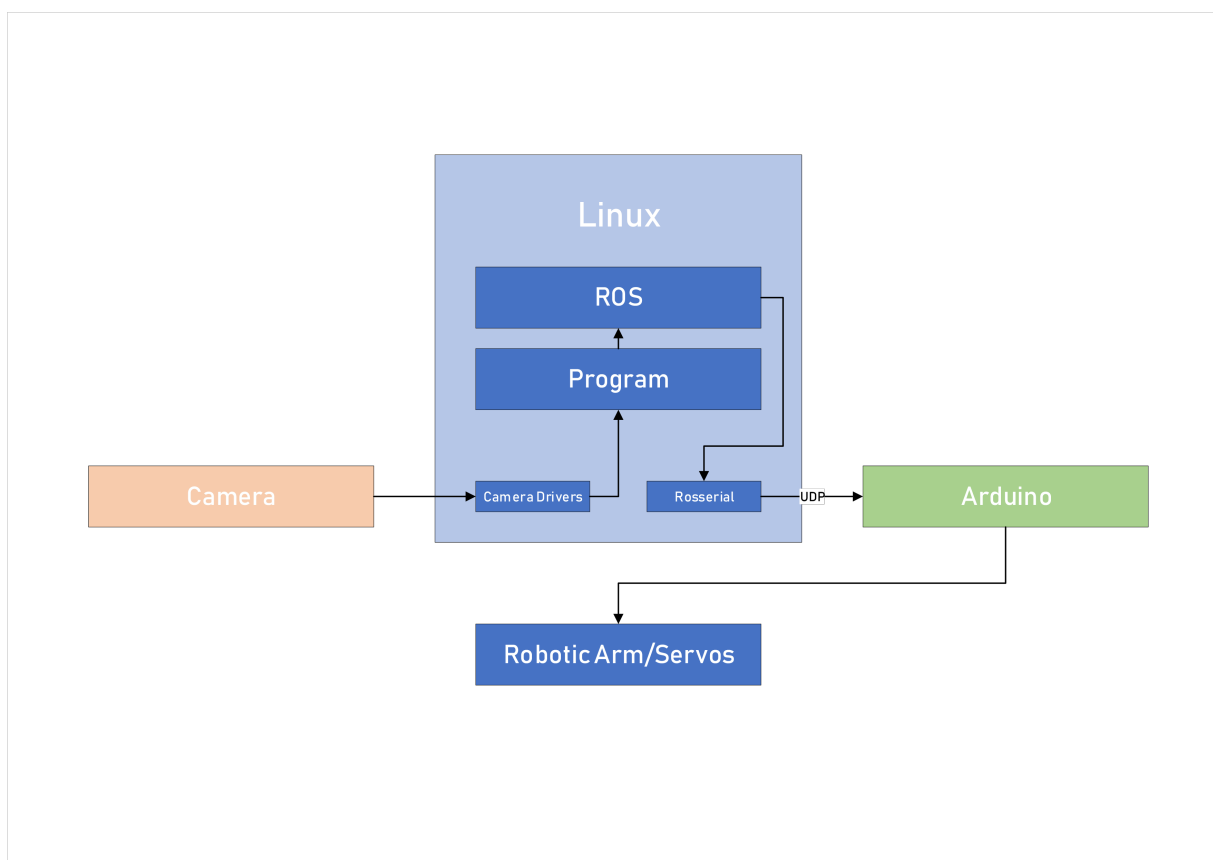

Figure 1: Simple diagram of communication

References

[1] ROS.org *Topics.* Link `http://wiki.ros.org/Topics` Read 08.02.2018