



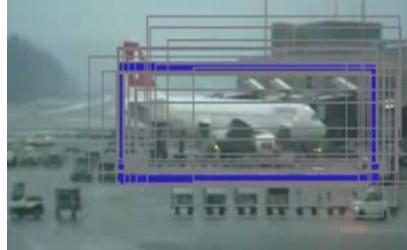
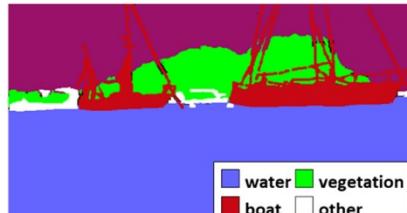
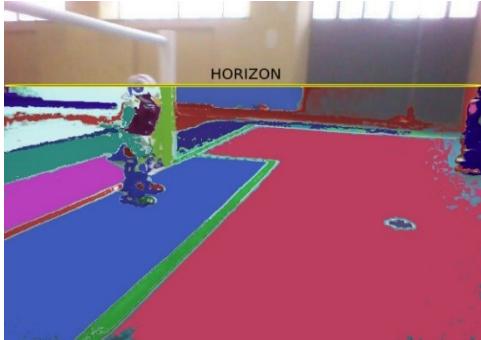
**UNIVERSITÀ DEGLI STUDI
DELLA BASILICATA**

Corso di Visione e Percezione
A.A. 2019/2020

Docente
Domenico Daniele Bloisi

ROS+OpenCV

Aprile 2020



Il corso

- Home page del corso
<http://web.unibas.it/bloisi/corsi/visione-e-percezione.html>
- Docente: Domenico Daniele Bloisi
- Periodo: Il semestre marzo 2020 – giugno 2020

Martedì 17:00-19:00 (Aula GUGLIELMINI)

Mercoledì 8:30-10:30 (Aula GUGLIELMINI)

References and credits

Alcune di queste slide si basano sul materiale contenuto nel libro

YoonSeok Pyo, HanCheol Cho, RyuWoon Jung, TaeHoon Lim,

“ROS Robot Programming - A Handbook Written by TurtleBot3 Developers”

<http://www.robotis.com/service/download.php?no=719>

rosbag

- I dati contenuti nei messaggi ROS possono essere registrati in appositi file
- Il file che contiene i messaggi prende il nome di **bag** e ha l'estensione “.bag”
- Il vantaggio offerto dai file di bag è quello di avere una registrazione che può essere utilizzata **più volte**, riproducendo ogni volta l'esatto scenario operativo in cui la bag è stata registrata

rosbag per i dati dei sensori

- Un esempio dell'utilità dei file di bag è dato dalla registrazione dei messaggi contenenti i dati prodotti dai sensori del robot
- Durante gli esperimenti con il robot reale, i dati dei sensori possono essere registrati in una bag
- I messaggi registrati possono essere poi caricati senza la necessità di ripetere l'esperimento, permettendo così di sviluppare con maggiore facilità algoritmi che richiedano modifiche frequenti dei parametri

Usare rosbag

rosbag è un package ROS per creare, riprodurre e comprimere bag di messaggi. Una bag è un file contenente i dati relativi a messaggi serializzati

- `rosbag record` → record all the topics
- `rosbag info bag-name` → info on the recorded bag
- `rosbag play --pause bag-name` → play the recorded bag, starting paused
- `rosbag play -r #number bag-name` → play the recorded bag at rate #number

Comandi rosbag

Command	Description
rosbag record [OPTION] [TOPIC_NAME]	Record the message of a specific topic on the bsg file
rosbag info [FILE_NAME]	Check information of a bag file
rosbag play [FILE_NAME]	Play a specific bag file
rosbag compress [FILE_NAME]	Compress a specific bag file
rosbag decompress [FILE_NAME]	Decompresses a specific bag file
rosbag filter [INPUT_FILE] [OUTPUT_FILE] [OPTION]	Create a new bag file with the specific content removed
rosbag reindex bag [FILE_NAME]	Reindex
rosbag check bag [FILE_NAME]	Check if the specific bag file can be played in the current system
rosbag fix [INPUT_FILE] [OUTPUT_FILE] [OPTION]	Fix the bag file version that was saved as an incompatible version

Esempio rosbag

Apriamo un terminal e digitiamo il comando roscore

```
roscore http://localhost:11311/
bloisi@bloisi-U36SG:~$ roscore
... logging to /home/bloisi/.ros/log/4d85da46-576b-11e8-9e4c-2709ac87ed01/roslaunch-bloisi-U36SG-2511.log
Checking log directory for disk usage. This may take awhile.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://localhost:38804/
ros_comm version 1.12.13

SUMMARY
=====

PARAMETERS
  * /rosdistro: kinetic
  * /rosversion: 1.12.13

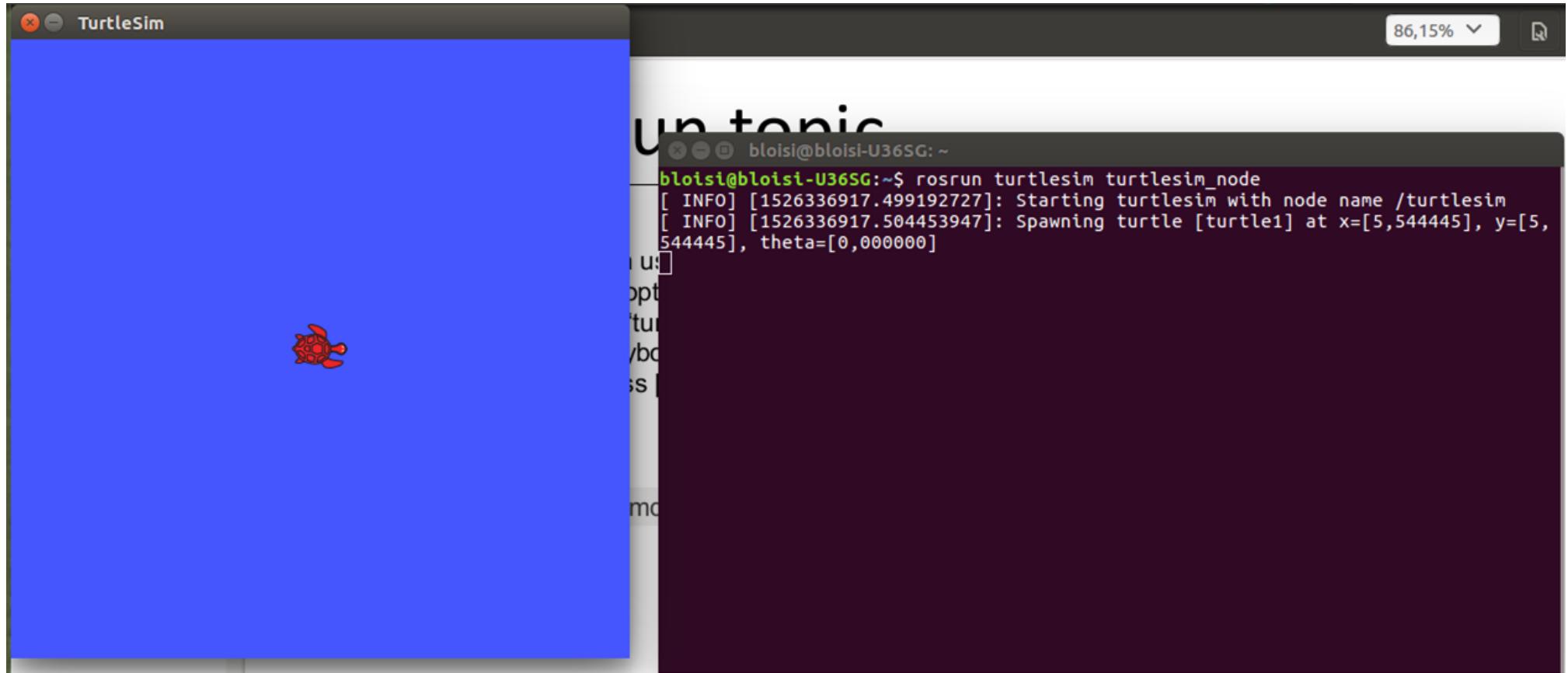
NODES

auto-starting new master
process[master]: started with pid [2523]
ROS_MASTER_URI=http://localhost:11311/

setting /run_id to 4d85da46-576b-11e8-9e4c-2709ac87ed01
process[rosout-1]: started with pid [2536]
started core service [/rosout]
```

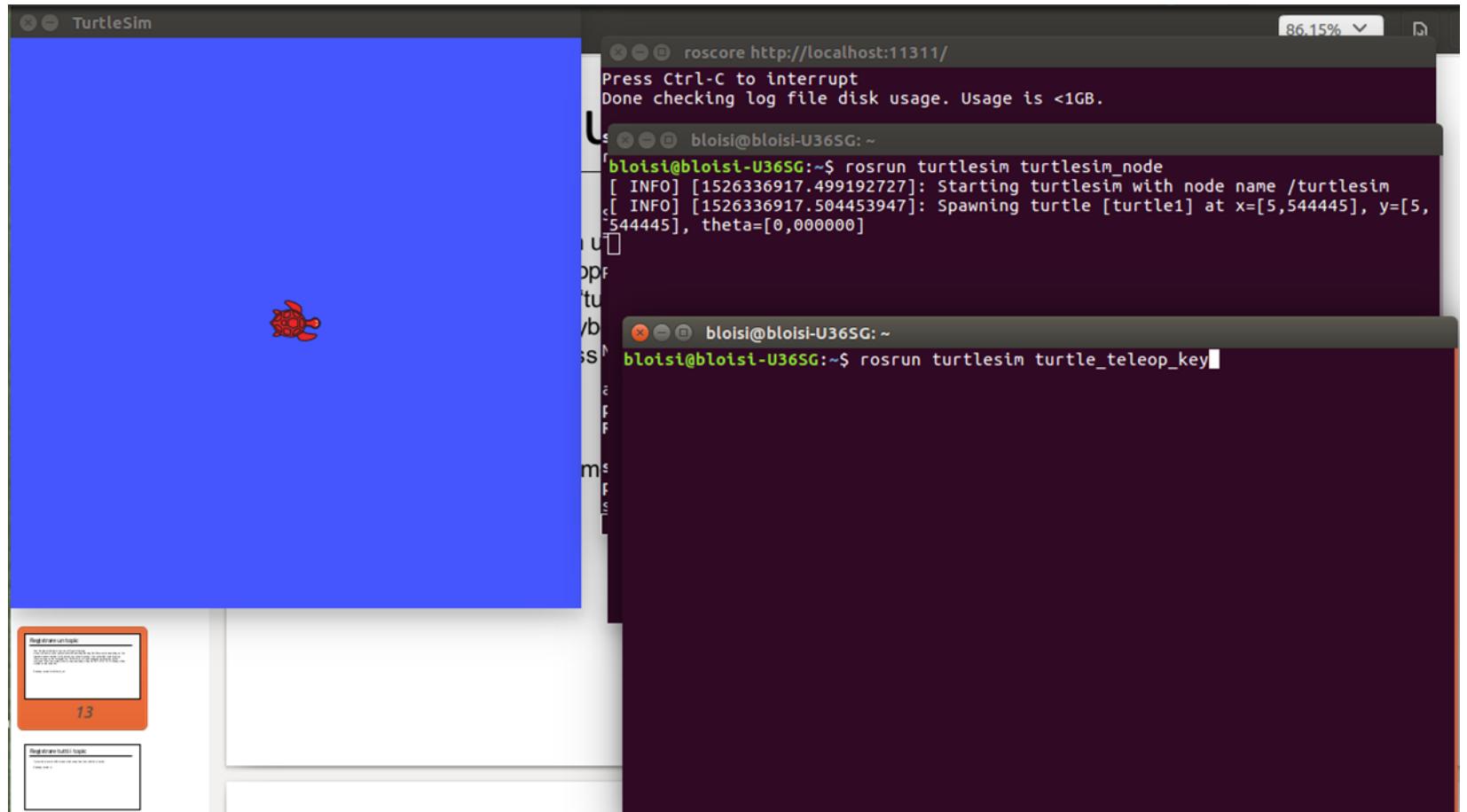
Esempio rosbag – turtlesim

Apriamo un secondo terminal e digitiamo
rosrun turtlesim turtlesim_node



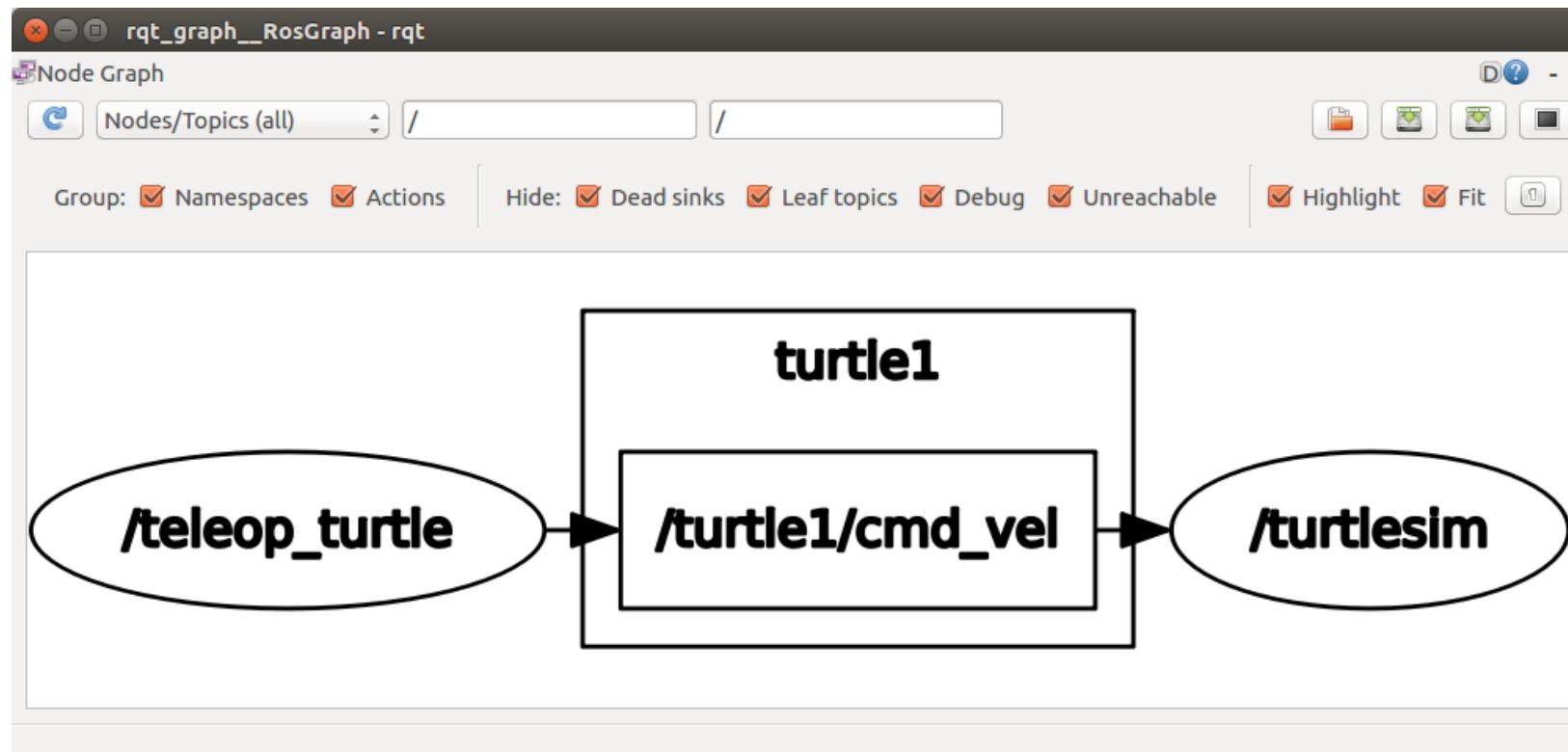
Esempio rosbag - teleop

Apriamo un terzo terminal e digitiamo
rosrun turtlesim turtle_teleop_key



rqt_graph

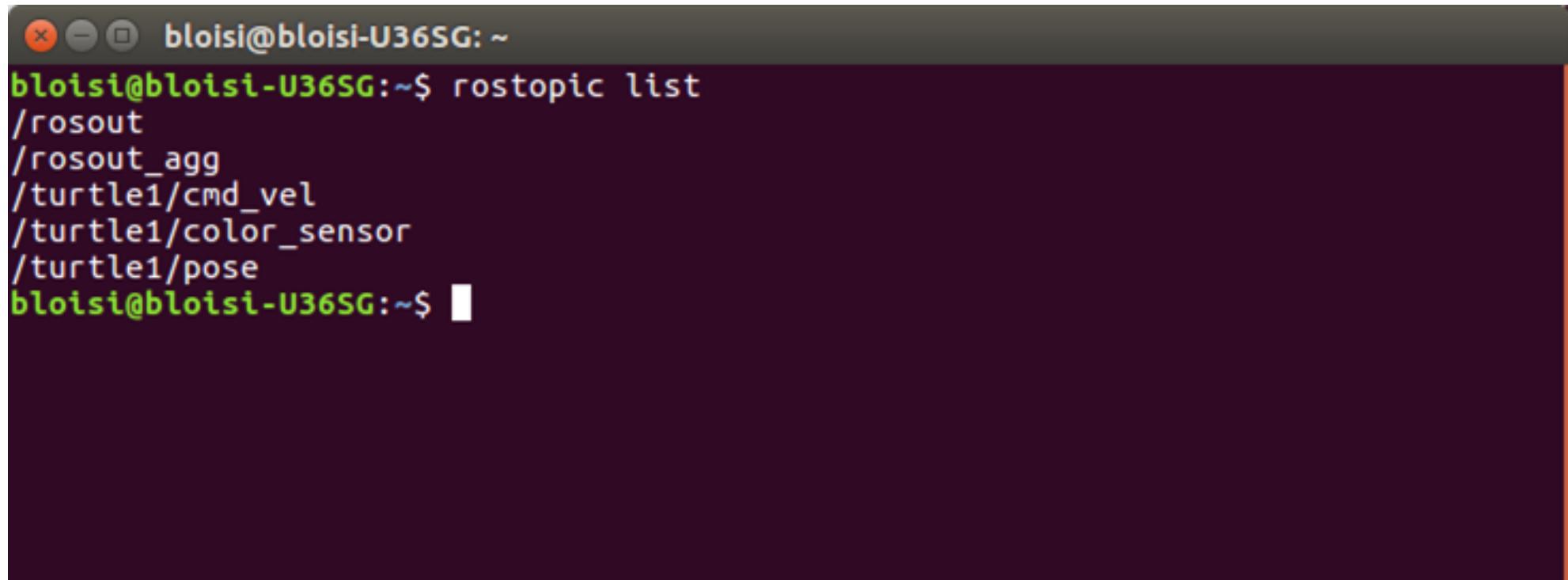
Apriamo un quarto terminal e digitiamo
rqt_graph
per verificare che i due nodi siano in collegamento tra loro



rostopic

Controlliamo anche a lista dei topic attivi

rostopic list

A screenshot of a terminal window titled "bloisi@bloisi-U36SG: ~". The window contains the command "rostopic list" followed by a list of active topics: /rosout, /rosout_agg, /turtle1/cmd_vel, /turtle1/color_sensor, and /turtle1/pose. The terminal has a dark background with light-colored text and standard window controls at the top.

```
bloisi@bloisi-U36SG: ~
bloisi@bloisi-U36SG:~$ rostopic list
/rosout
/rosout_agg
/turtle1/cmd_vel
/turtle1/color_sensor
/turtle1/pose
bloisi@bloisi-U36SG:~$
```

Registrare un topic

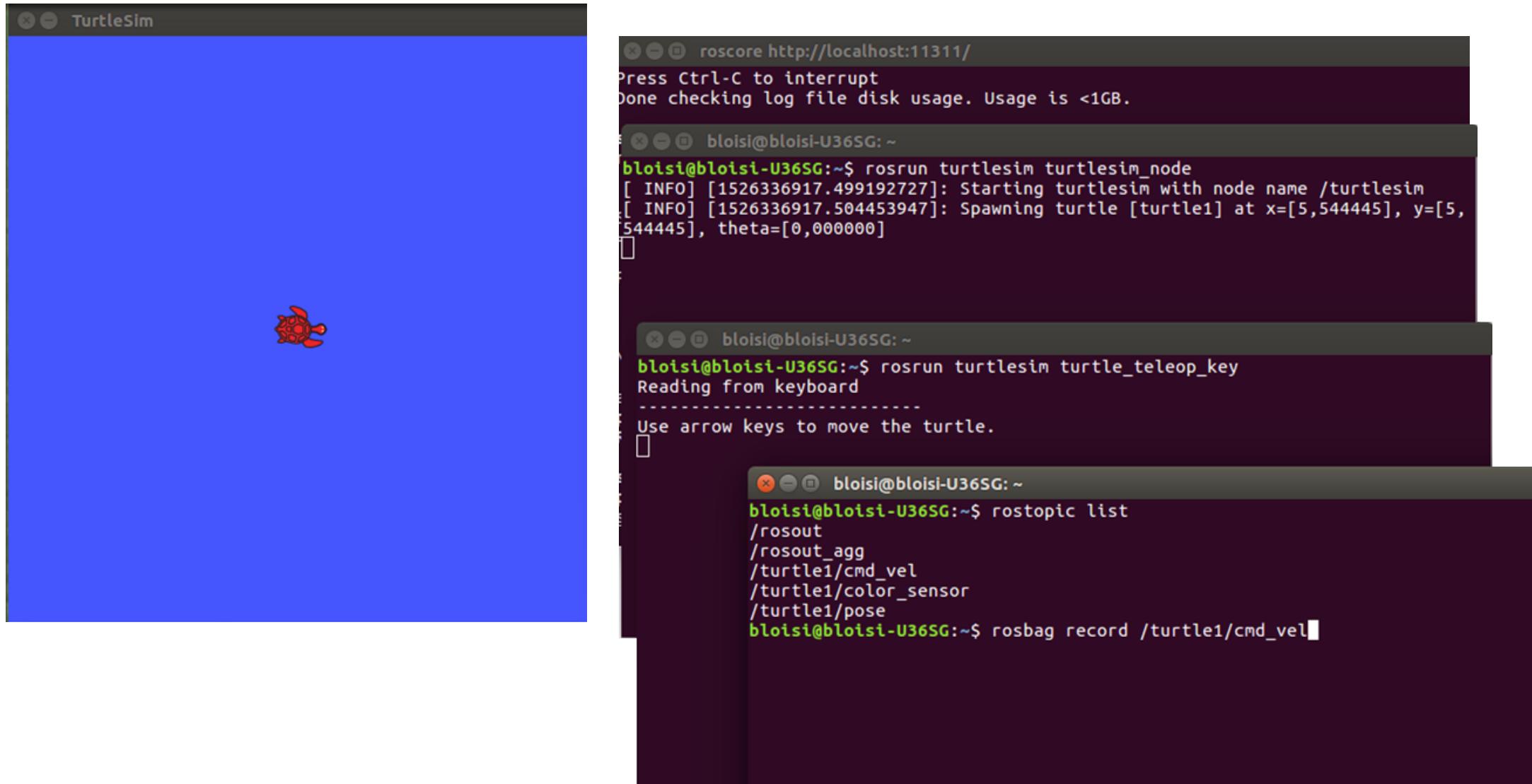
Tra tutti i topic attivi, possiamo scegliere quali registrare usando i comandi e le opzioni di rosbag

```
rosbag record <topic name>
```

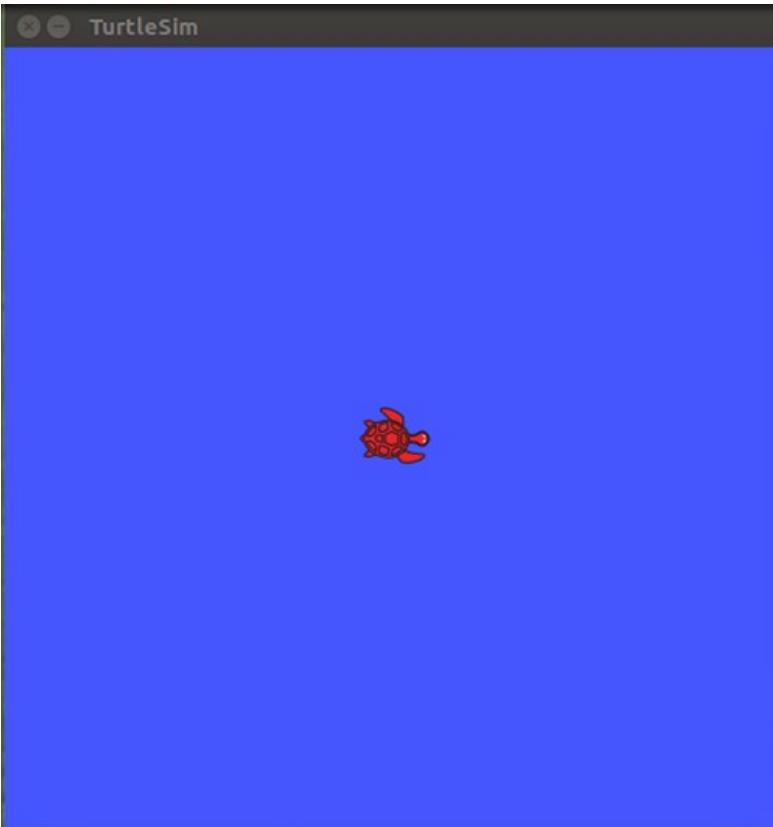
Per esempio, per registrare i comandi inviati tramite cmd_vel
digitiamo

```
rosbag record /turtle1/cmd_vel
```

Esempio - Registrare un topic



Esempio – Registrazione in corso...



```
roscore http://localhost:11311/  
Press Ctrl-C to interrupt  
Done checking log file disk usage. Usage is <1GB.  
  
bloisi@bloisi-U36SG:~$ rosrun turtlesim turtlesim_node  
[ INFO] [1526336917.499192727]: Starting turtlesim with node name /turtlesim  
[ INFO] [1526336917.504453947]: Spawning turtle [turtle1] at x=[5,544445], y=[5,  
544445], theta=[0,000000]  
  
bloisi@bloisi-U36SG:~$ rosrun turtlesim turtle_teleop_key  
Reading from keyboard  
-----  
Use arrow keys to move the turtle.  
  
bloisi@bloisi-U36SG:~$ rostopic list  
/rosout  
/rosout_agg  
/turtle1/cmd_vel  
/turtle1/color_sensor  
/turtle1/pose  
bloisi@bloisi-U36SG:~$ rosbag record /turtle1/cmd_vel  
[ INFO] [1526337037.406675213]: Subscribing to /turtle1/cmd_vel  
[ INFO] [1526337037.414123426]: Recording to 2018-05-15-00-30-37.bag.
```

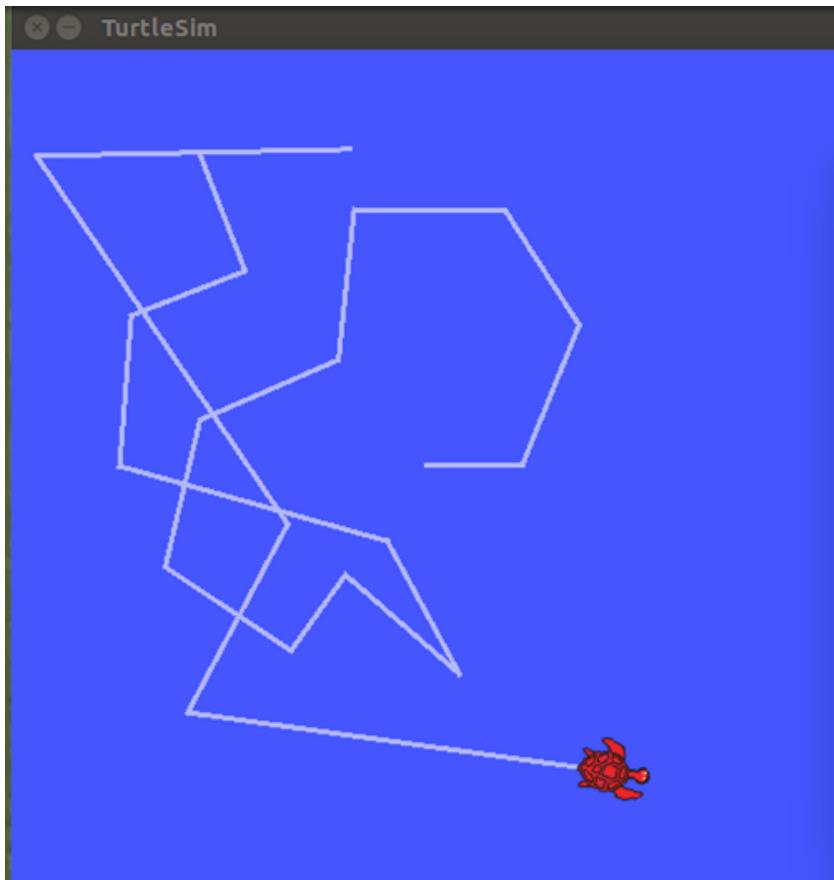
Registrare tutti i topic

Se si vogliono registrare tutti i topic attivi, si può usare l'opzione -a

```
rosbag record -a
```

Terminare la registrazione

[Ctrl-C] ci permette di terminare la registrazione della bag

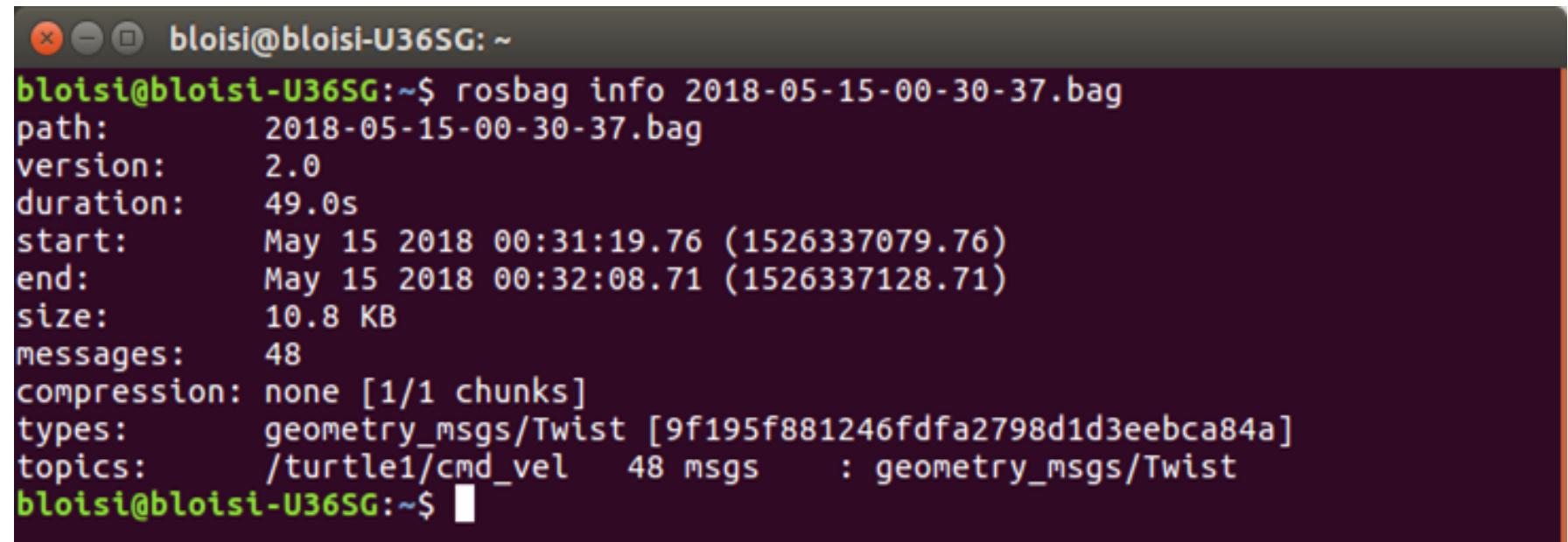


```
bloisi@bloisi-U36SG:~$ rostopic list
/rosout
/rosout_agg
/turtle1/cmd_vel
/turtle1/color_sensor
/turtle1/pose
bloisi@bloisi-U36SG:~$ rosbag record /turtle1/cmd_vel
[ INFO] [1526337037.406675213]: Subscribing to /turtle1/cmd_vel
[ INFO] [1526337037.414123426]: Recording to 2018-05-15-00-30-37.bag.
^Cbloisi@bloisi-U36SG:~$
```

rosbag info

- Il comando `info` stampa a video informazioni sulla bag fornita come parametro
- Ad esempio, avremo informazioni sul file `2018-05-15-00-30-37.bag` digitando

```
rosbag info 2018-05-15-00-30-37.bag
```



The screenshot shows a terminal window with a dark background and light-colored text. The title bar reads "bloisi@bloisi-U36SG: ~". The command entered is "rosbag info 2018-05-15-00-30-37.bag". The output provides detailed information about the bag file:

```
bloisi@bloisi-U36SG:~$ rosbag info 2018-05-15-00-30-37.bag
path:      2018-05-15-00-30-37.bag
version:   2.0
duration:  49.0s
start:     May 15 2018 00:31:19.76 (1526337079.76)
end:      May 15 2018 00:32:08.71 (1526337128.71)
size:     10.8 KB
messages:  48
compression: none [1/1 chunks]
types:    geometry_msgs/Twist [9f195f881246fd8a2798d1d3eebca84a]
topics:   /turtle1/cmd_vel  48 msgs  : geometry_msgs/Twist
bloisi@bloisi-U36SG:~$
```

rosbag play

Avendo a disposizione una bag registrata, si può riprodurla tramite

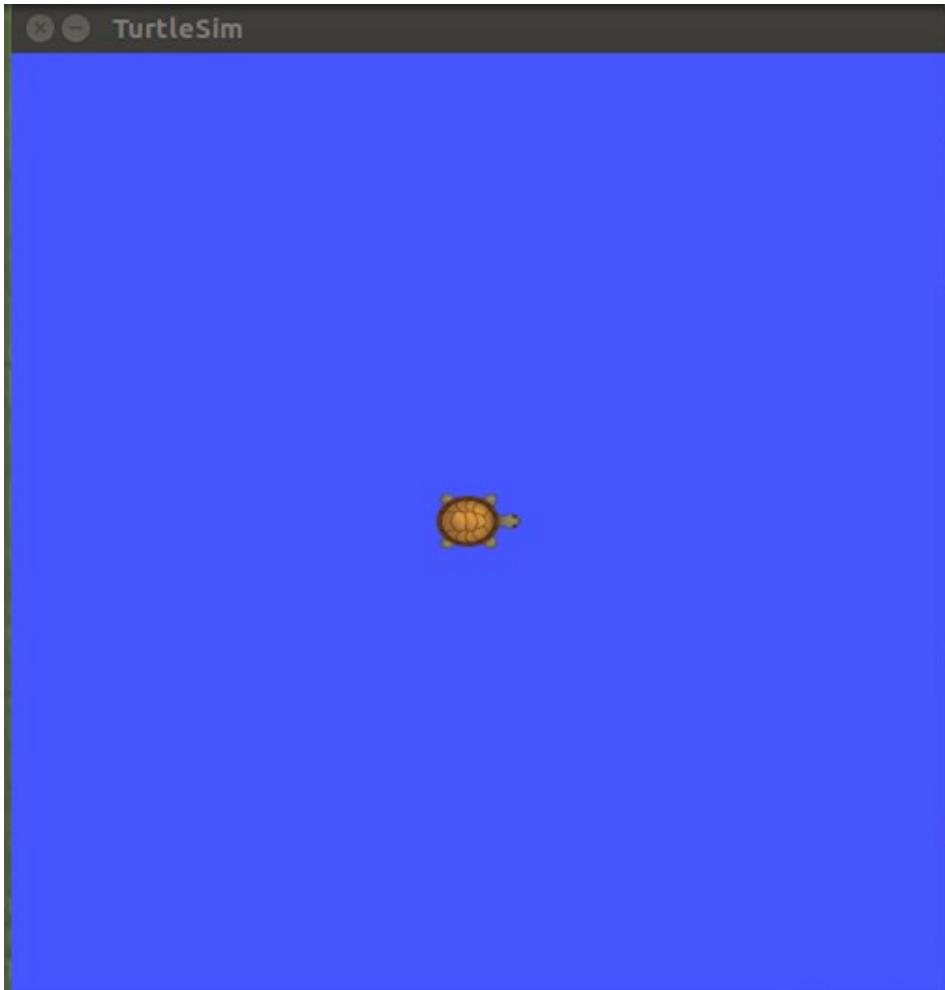
```
rosbag play <bagfile name>
```

Per riprodurre la bag 2018-05-15-00-30-37.bag:

1. Terminiamo tutti i nodi attivi
2. Lanciamo il nodo turtlesim_node
3. Digitiamo il comando

```
rosbag play 2018-05-15-00-30-37.bag
```

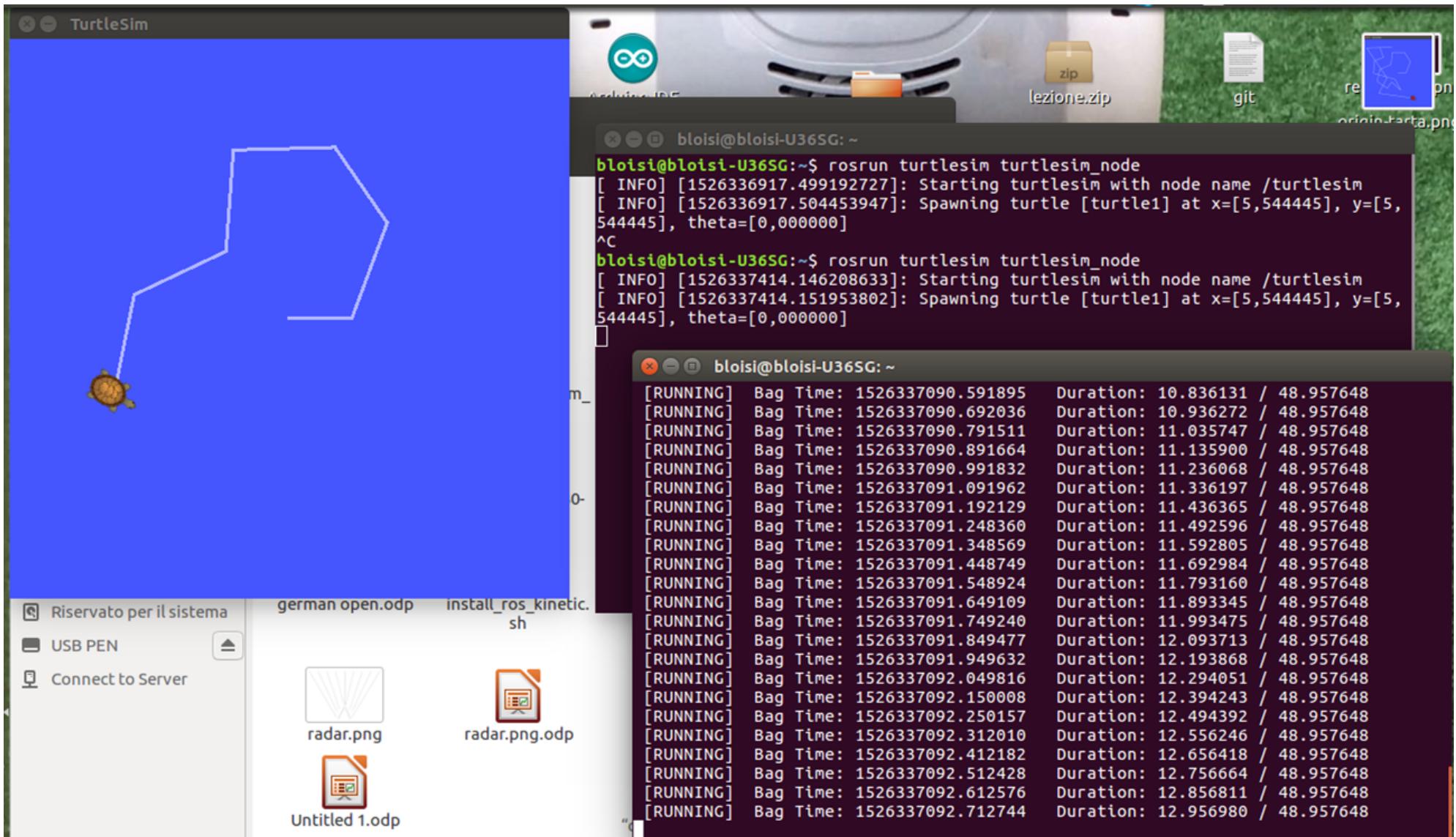
rosbag play – esecuzione



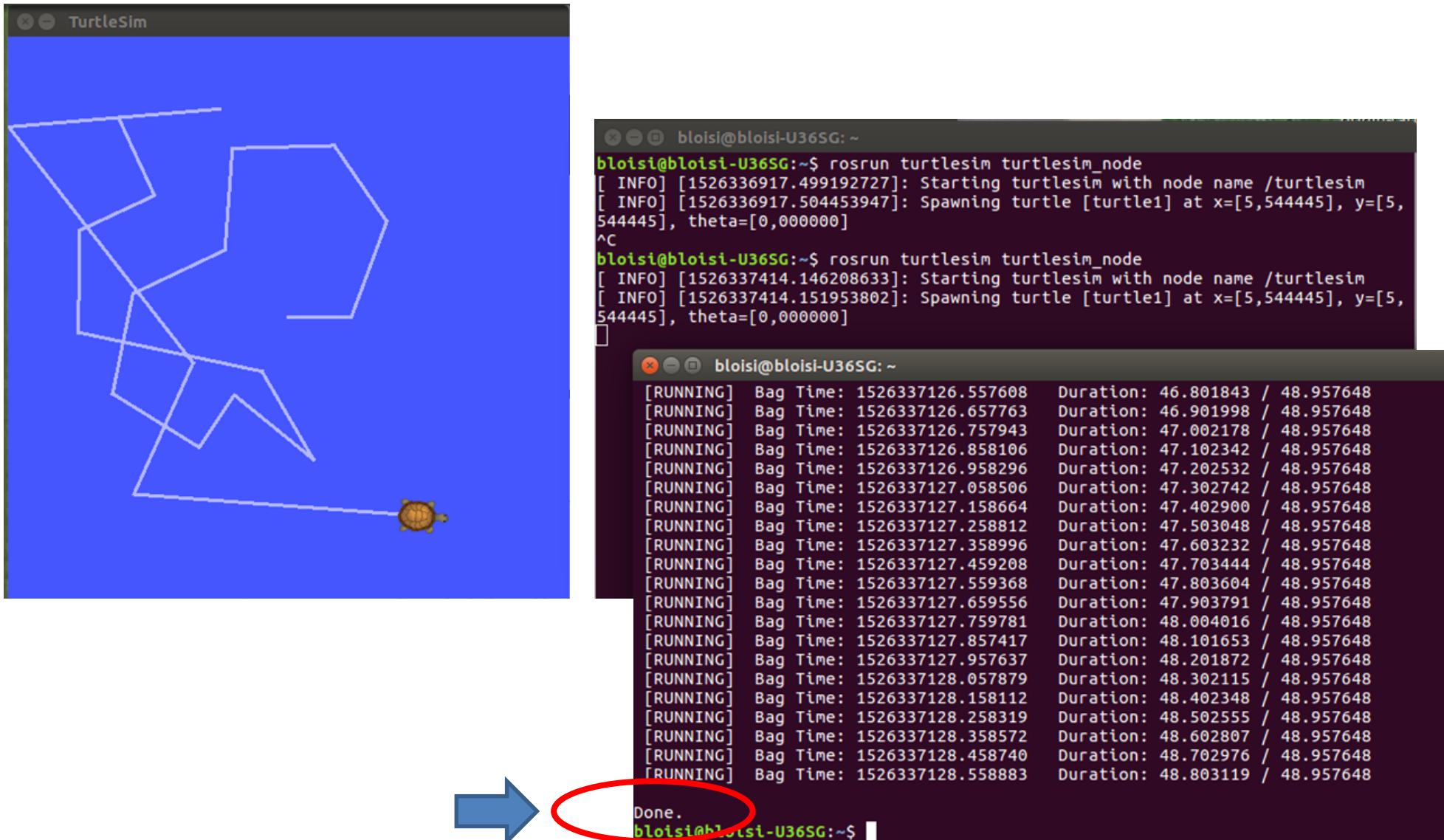
```
bloisi@bloisi-U36SG:~$ rosrun turtlesim turtlesim_node
[ INFO] [1526336917.499192727]: Starting turtlesim with node name /turtlesim
[ INFO] [1526336917.504453947]: Spawning turtle [turtle1] at x=[5,544445], y=[5,544445], theta=[0,000000]
^C
bloisi@bloisi-U36SG:~$ rosrun turtlesim turtlesim_node
[ INFO] [1526337414.146208633]: Starting turtlesim with node name /turtlesim
[ INFO] [1526337414.151953802]: Spawning turtle [turtle1] at x=[5,544445], y=[5,544445], theta=[0,000000]
[ ]
```

```
bloisi@bloisi-U36SG:~$ rosbag play 2018-05-15-00-30-37.bag
```

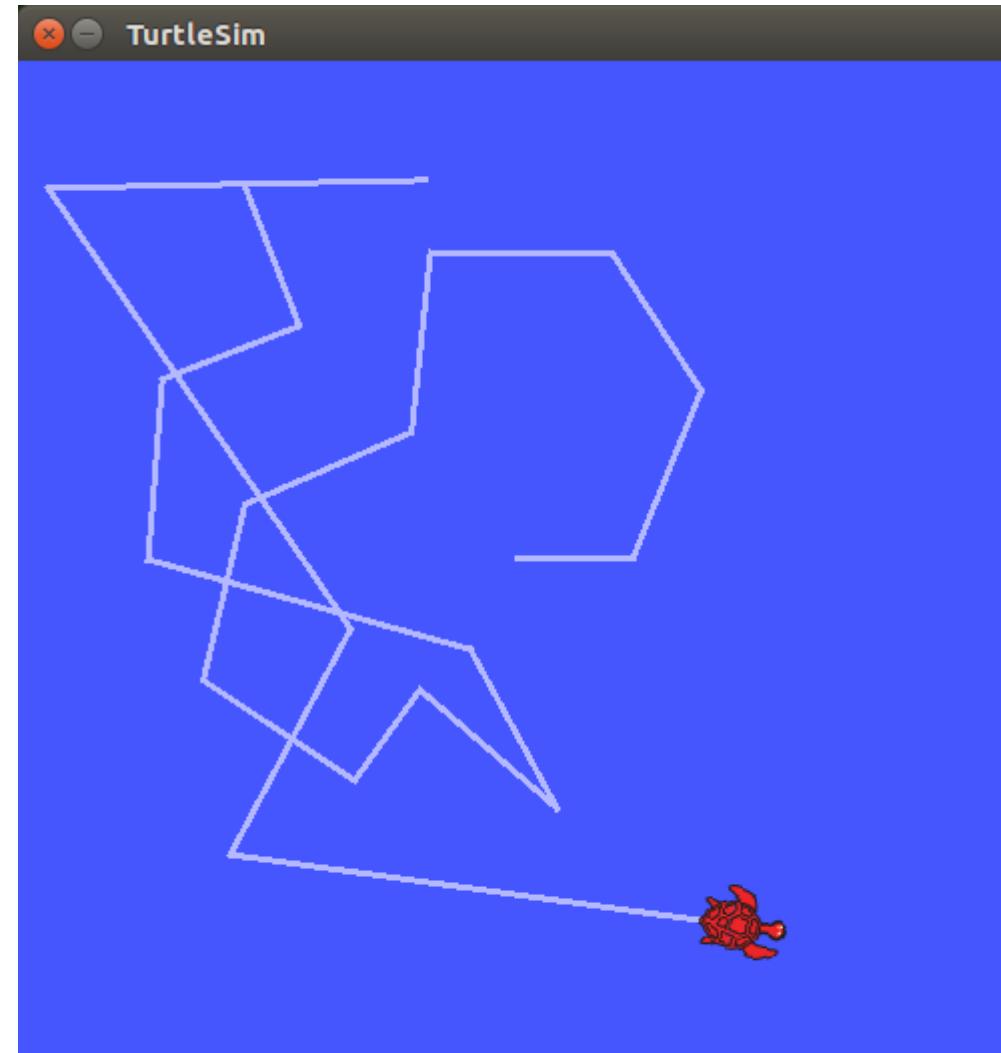
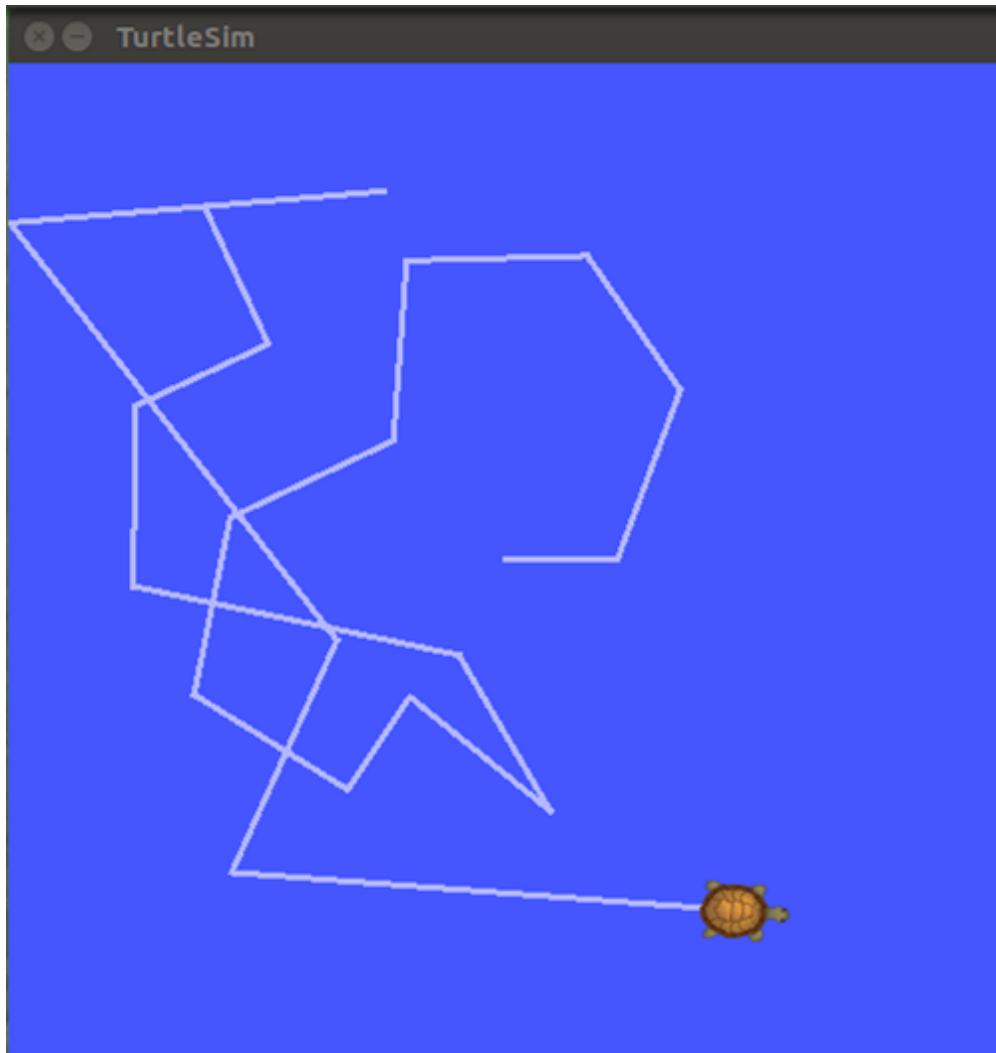
rosbag play – esecuzione in corso



rosbag play – risultato finale



rosbag play – confronto



I bag file possono essere molto grandi

Un bag file registrato per un breve periodo di tempo comporta la creazione di file aventi dimensioni contenute

Se, invece, si ha bisogno di registrare messaggi per un lungo periodo di tempo, allora la dimensione del bag file può crescere fino ad occupare molta memoria

Si provi per esempio a scaricare la ROS bag a questo indirizzo

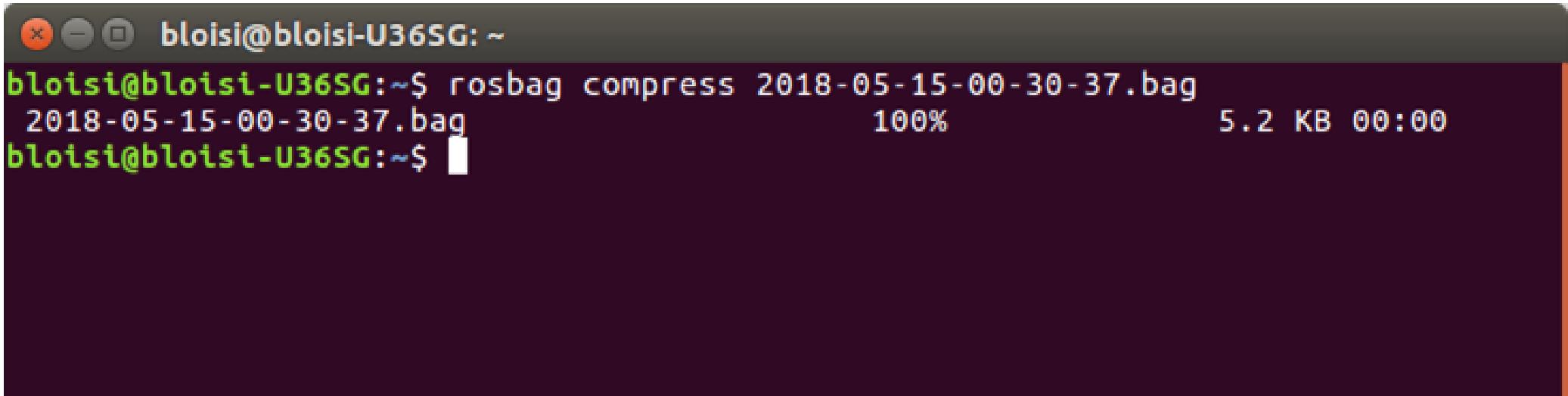
https://drive.google.com/file/d/1F8pd_Cc5n67cMkWdvTZphpi7zecRJDEJ/view?usp=sharing

rosbag compress

ROS fornisce la possibilità di comprimere i bag file grazie all'opzione compress

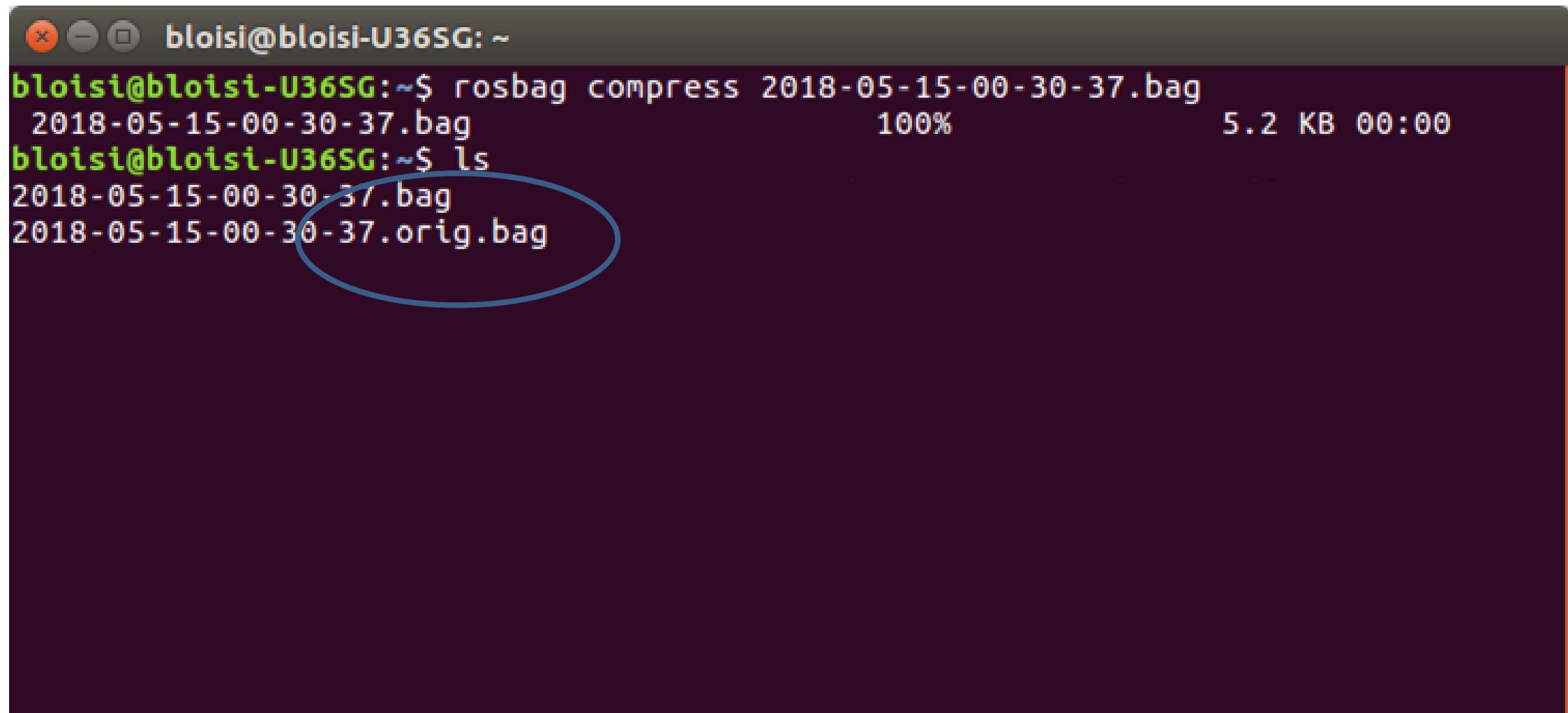
Esempio

```
rosbag compress 2018-05-15-00-30-37.bag
```



The screenshot shows a terminal window with a dark background and light-colored text. The window title bar reads "bloisi@bloisi-U36SG: ~". The command entered is "rosbag compress 2018-05-15-00-30-37.bag". To the right of the command, progress indicators are shown: "100%", "5.2 KB", and "00:00". The bottom of the terminal window shows the prompt "bloisi@bloisi-U36SG:~\$".

rosbag compress – esecuzione



The screenshot shows a terminal window with a dark background and light-colored text. The terminal title is "bloisi@bloisi-U36SG: ~". The user runs the command "rosbag compress 2018-05-15-00-30-37.bag". The output shows the progress: "100%" and "5.2 KB 00:00". After the compression, the user runs "ls" to list the files, which shows "2018-05-15-00-30-37.bag" and "2018-05-15-00-30-37.orig.bag". A blue oval highlights the two listed files.

```
bloisi@bloisi-U36SG: ~
bloisi@bloisi-U36SG: ~$ rosbag compress 2018-05-15-00-30-37.bag
2018-05-15-00-30-37.bag                                         100%          5.2 KB 00:00
bloisi@bloisi-U36SG: ~$ ls
2018-05-15-00-30-37.bag
2018-05-15-00-30-37.orig.bag
```

rosbag decompress

Per riportare il bag file al suo formato originale è possibile utilizzare decompress

```
rosbag decompress 2018-05-15-00-30-37.bag
```

rosbag con immagini

- Una bag può contenere qualunque tipo di dato sia possibile inviare tramite i messaggi ROS
- Le bag possono essere molto utili per la registrazione di dati provenienti da telecamere montate su robot
- In particolare, essendo presente un timestamp per ogni immagine, è possibile riprodurre fedelmente lo stream dati del sensore usato per effettuare le riprese

Image message

[sensor_msgs/](#)Image Message

File: [sensor_msgs/Image.msg](#)

Raw Message Definition

```
# This message contains an uncompressed image
# (0, 0) is at top-left corner of image
#
Header header      # Header timestamp should be acquisition time of image
                    # Header frame_id should be optical frame of camera
                    # origin of frame should be optical center of camera
                    # +x should point to the right in the image
                    # +y should point down in the image
                    # +z should point into to plane of the image
                    # If the frame_id here and the frame_id of the CameraInfo
                    # message associated with the image conflict
                    # the behavior is undefined
uint32 height       # image height, that is, number of rows
uint32 width        # image width, that is, number of columns
#
# The legal values for encoding are in file src/image_encodings.cpp
# If you want to standardize a new string format, join
# ros-users@lists.sourceforge.net and send an email proposing a new encoding.
string encoding     # Encoding of pixels -- channel meaning, ordering, size
                    # taken from the list of strings in include/sensor_msgs/image_encodings.h
```

cv_bridge



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[vision_opencv](#): [cv_bridge](#) | [image_geometry](#)

Package Summary

Released Continuous Integration Documented

This contains CvBridge, which converts between ROS Image messages and OpenCV images.

- Maintainer status: maintained
- Maintainer: Vincent Rabaud <vincent.rabaud AT gmail DOT com>
- Author: Patrick Mihelich, James Bowman
- License: BSD
- Bug / feature tracker: https://github.com/ros-perception/vision_opencv/issues
- Source: git https://github.com/ros-perception/vision_opencv.git (branch: kinetic)

Package Links

[Code API](#)

[Tutorials](#)

[FAQ](#)

[Changelog](#)

[Change List](#)

[Reviews](#)

Dependencies (4)

[Used by \(128\)](#)

[Jenkins jobs \(10\)](#)

Wiki

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[ROS/Tutorials](#)

[RecentChanges](#)

[cv_bridge](#)

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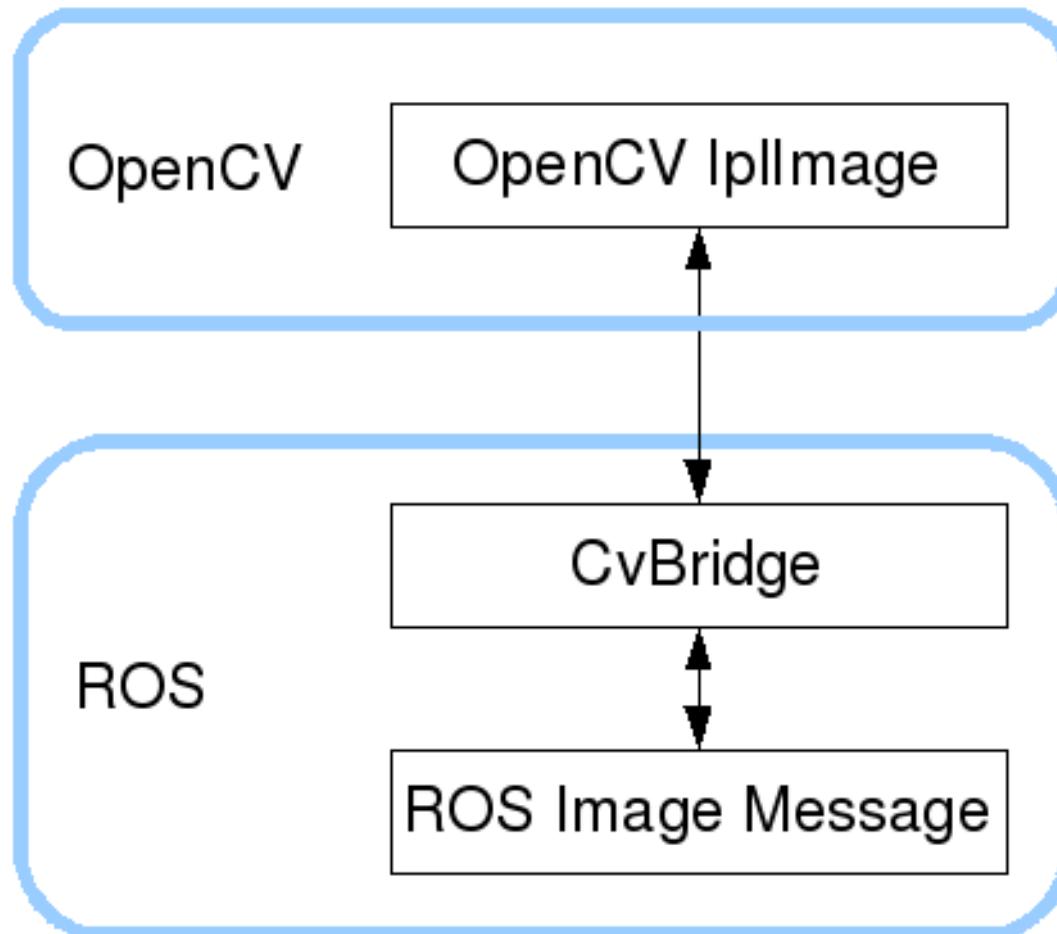
[Allegati](#)

Altre azioni:

Utente

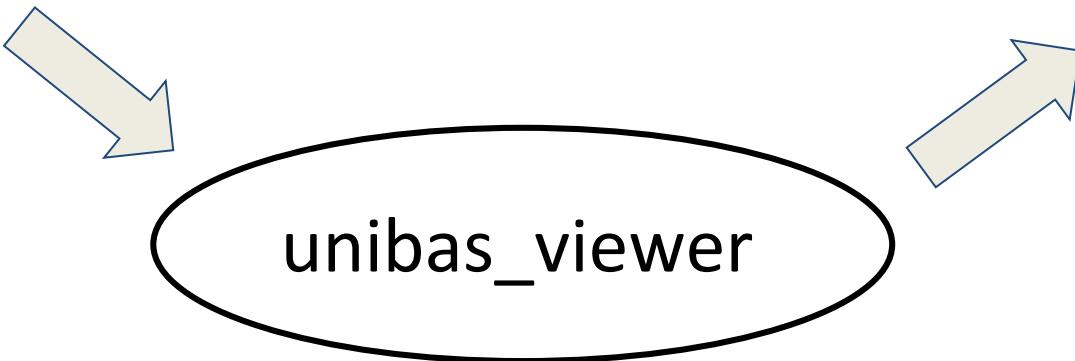
[Accedi](#)

cv_bridge



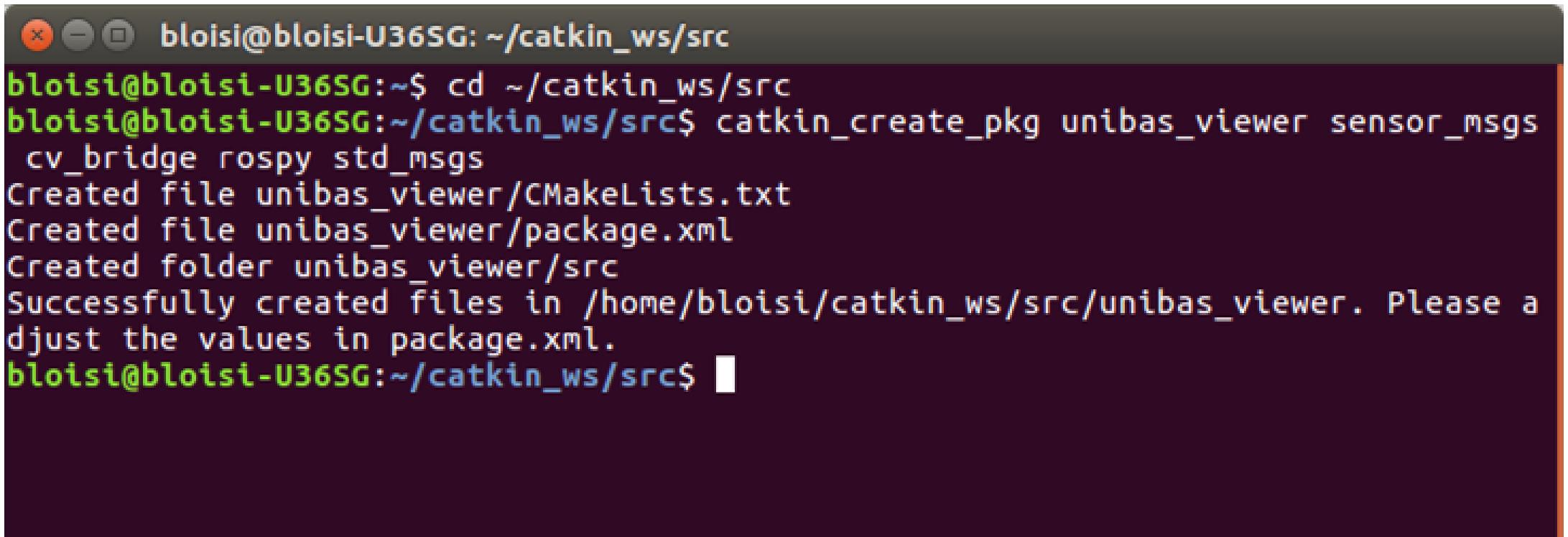
Esempio: unibas_viewer

rosbag acquisita con
un sensore RGBD



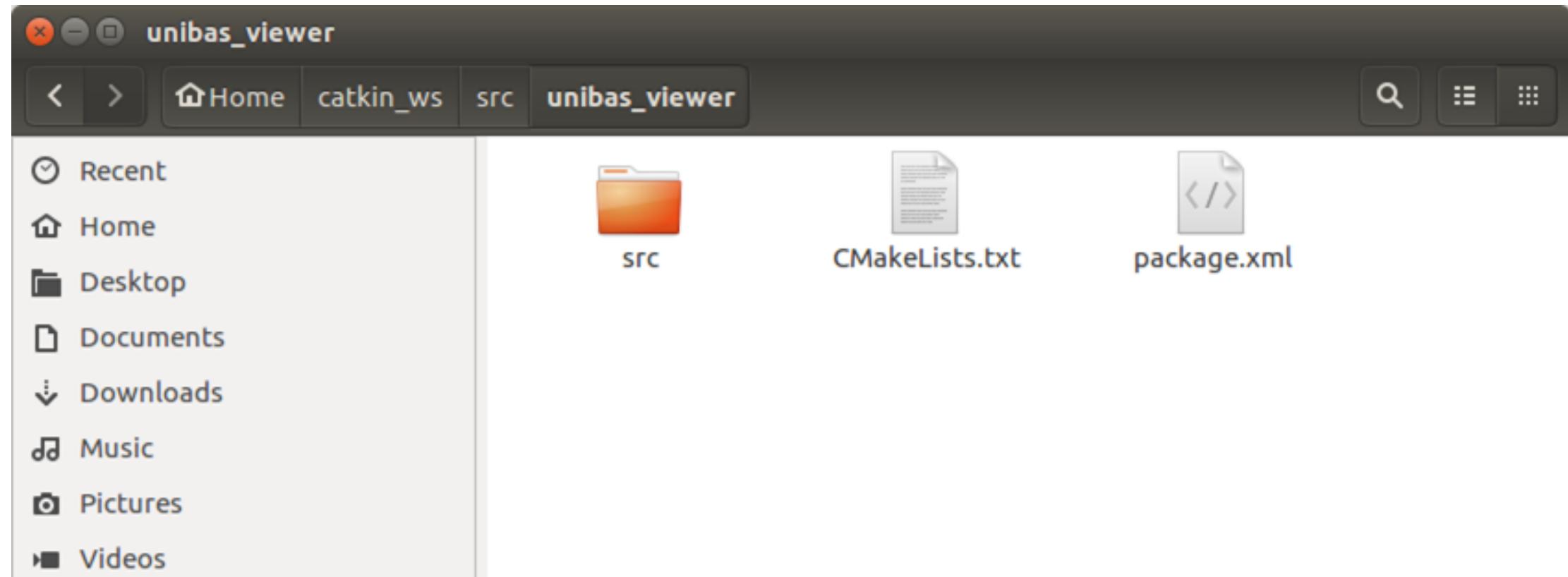
visualizzazione dati
color + depth
con OpenCV

creazione del nodo unibas_viewer



```
bloisi@bloisi-U36SG: ~/catkin_ws/src
bloisi@bloisi-U36SG:~/catkin_ws/src$ cd ~/catkin_ws/src
bloisi@bloisi-U36SG:~/catkin_ws/src$ catkin_create_pkg unibas_viewer sensor_msgs
cv_bridge rospy std_msgs
Created file unibas_viewer/CMakeLists.txt
Created file unibas_viewer/package.xml
Created folder unibas_viewer/src
Successfully created files in /home/bloisi/catkin_ws/src/unibas_viewer. Please adjust the values in package.xml.
bloisi@bloisi-U36SG:~/catkin_ws/src$
```

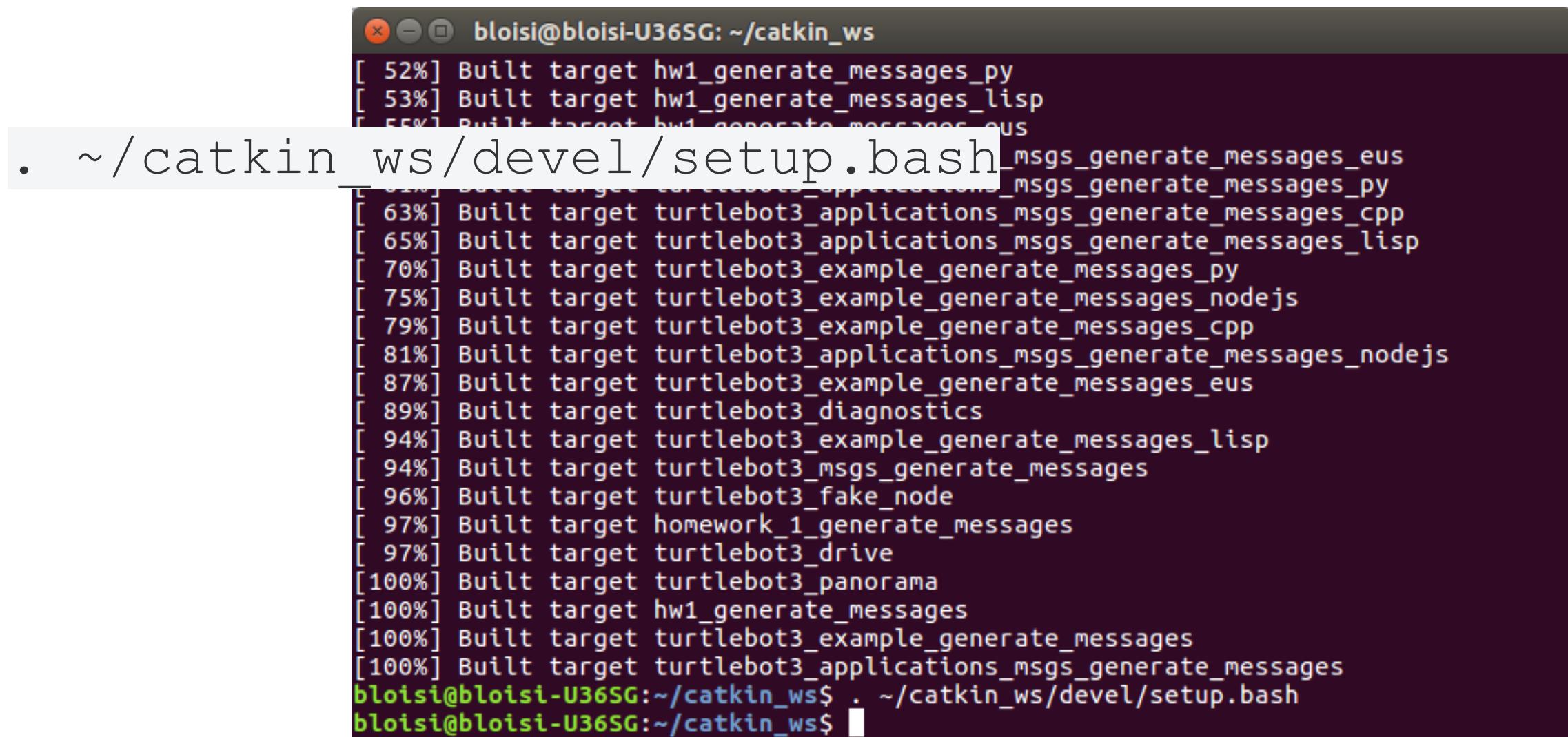
cartella unibas_viewer



catkin_make

```
bloisi@bloisi-U36SG: ~/catkin_ws
bloisi@bloisi-U36SG:~$ cd ~/catkin_ws/src
bloisi@bloisi-U36SG:~/catkin_ws/src$ catkin_create_pkg unibas_viewer sensor_msgs
cv_bridge rospy std_msgs
Created file unibas_viewer/CMakeLists.txt
Created file unibas_viewer/package.xml
Created folder unibas_viewer/src
Successfully created files in /home/bloisi/catkin_ws/src/unibas_viewer. Please adjust the values in package.xml.
bloisi@bloisi-U36SG:~/catkin_ws/src$ cd ..
bloisi@bloisi-U36SG:~/catkin_ws$ catkin_make
```

settiamo l'ambiente ROS



A screenshot of a terminal window titled "bloisi@bloisi-U36SG: ~/catkin_ws". The window shows the progress of a "catkin build" command. The output text is as follows:

```
[ 52%] Built target hw1_generate_messages_py
[ 53%] Built target hw1_generate_messages_lisp
[ 55%] Built target hw1_generate_messages_eus
.
. ~/catkin_ws/devel/setup.bash
[ 61%] Built target turtlebot3_applications_msgs_generate_messages_py
[ 63%] Built target turtlebot3_applications_msgs_generate_messages_cpp
[ 65%] Built target turtlebot3_applications_msgs_generate_messages_lisp
[ 70%] Built target turtlebot3_example_generate_messages_py
[ 75%] Built target turtlebot3_example_generate_messages_nodejs
[ 79%] Built target turtlebot3_example_generate_messages_cpp
[ 81%] Built target turtlebot3_applications_msgs_generate_messages_nodejs
[ 87%] Built target turtlebot3_example_generate_messages_eus
[ 89%] Built target turtlebot3_diagnostics
[ 94%] Built target turtlebot3_example_generate_messages_lisp
[ 94%] Built target turtlebot3_msgs_generate_messages
[ 96%] Built target turtlebot3_fake_node
[ 97%] Built target homework_1_generate_messages
[ 97%] Built target turtlebot3_drive
[100%] Built target turtlebot3_panorama
[100%] Built target hw1_generate_messages
[100%] Built target turtlebot3_example_generate_messages
[100%] Built target turtlebot3_applications_msgs_generate_messages
bloisi@bloisi-U36SG:~/catkin_ws$ . ~/catkin_ws/devel/setup.bash
bloisi@bloisi-U36SG:~/catkin_ws$ █
```

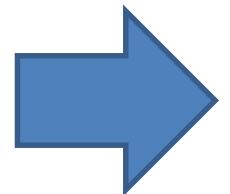
https://answers.ros.org/question/229365/do-i-really-need-to-source-catkin_wsdevelsetupbash/

rospack find

```
[ 58%] Built target turtlebot3_applications_msgs_generate_messages_eus
[ 61%] Built target turtlebot3_applications_msgs_generate_messages_py
[ 63%] Built target turtlebot3_applications_msgs_generate_messages_cpp
[ 65%] Built target turtlebot3_applications_msgs_generate_messages_lisp
[ 70%] Built target turtlebot3_example_generate_messages_py
[ 75%] Built target turtlebot3_example_generate_messages_nodejs
[ 79%] Built target turtlebot3_example_generate_messages_cpp
[ 81%] Built target turtlebot3_applications_msgs_generate_messages_nodejs
[ 87%] Built target turtlebot3_example_generate_messages_eus
rospack find unibas_viewer
[ 94%] Built target turtlebot3_msgs_generate_messages
[ 96%] Built target turtlebot3_fake_node
[ 97%] Built target homework_1_generate_messages
[ 97%] Built target turtlebot3_drive
[100%] Built target turtlebot3_panorama
[100%] Built target hw1_generate_messages
[100%] Built target turtlebot3_example_generate_messages
[100%] Built target turtlebot3_applications_msgs_generate_messages
bloisi@bloisi-U36SG:~/catkin_ws$ . ~/catkin_ws/devel/setup.bash
bloisi@bloisi-U36SG:~/catkin_ws$ rospack find unibas_viewer
/home/bloisi/catkin_ws/src/unibas_viewer
```

creiamo unibas_rgbd_reader.py

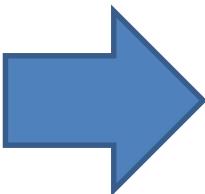
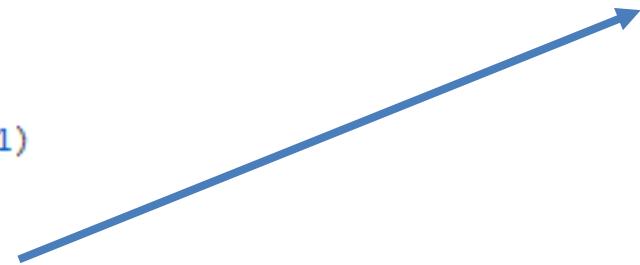
```
1 #!/usr/bin/env python
2 from __future__ import print_function
3
4 import roslib
5 roslib.load_manifest('unibas_viewer')
6 import sys
7 import rospy
8 import cv2
9 import numpy as np
10 import message_filters
11 from std_msgs.msg import String
12 from sensor_msgs.msg import Image
13 from cv_bridge import CvBridge, CvBridgeError
14
15 class unibas_rgbd_reader:
```



creiamo unibas_rgbd_reader.py

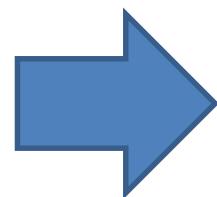
```
16
17     def __init__(self):
18         self.bridge = CvBridge()
19         self.image_sub = message_filters.Subscriber("/camera/rgb/image_raw",Image)
20         self.depth_sub = message_filters.Subscriber("/camera/depth_registered/image_raw",Image)
21         self.ts = message_filters.ApproximateTimeSynchronizer([self.image_sub, self.depth_sub], queue_size=10, slop=0.5)
22         self.ts.registerCallback(self.callback)
23
24         self.pub = rospy.Publisher('/unibas_viewer/rgbd', Image, queue_size=1)
25
```

the slop parameter defines the delay (in seconds) with which messages can be synchronized



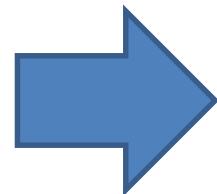
creiamo unibas_rgbd_reader.py

```
26     def callback(self, rgb_data, depth_data):  
27  
28         try:  
29             cv_image = self.bridge.imgmsg_to_cv2(rgb_data, "bgr8")  
30             depth_image = self.bridge.imgmsg_to_cv2(depth_data, "32FC1")  
31             depth_array = np.array(depth_image, dtype=np.float32)  
32             cv2.normalize(depth_array, depth_array, 0, 1, cv2.NORM_MINMAX)  
33             depth_8 = (depth_array * 255).round().astype(np.uint8)  
34             cv_depth = np.zeros_like(cv_image)  
35             cv_depth[:, :, 0] = depth_8  
36             cv_depth[:, :, 1] = depth_8  
37             cv_depth[:, :, 2] = depth_8  
38  
39         except CvBridgeError as e:  
40             print(e)  
41  
42         rgbd = np.concatenate((cv_image, cv_depth), axis=1)  
43
```



creiamo unibas_rgbd_reader.py

```
44     #cv2.imshow("res", res)
45     #cv2.waitKey(30)
46
47     #convert opencv format back to ros format and publish result
48     try:
49         rgbd_message = self.bridge.cv2_to_imgmsg(rgbd, "bgr8")
50         self.pub.publish(rgbd_message)
51     except CvBridgeError as e:
52         print(e)
53
54
```

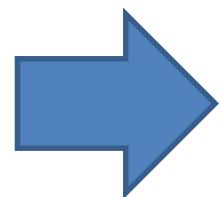


creiamo unibas_rgbd_reader.py

```
55
56  def main(args):
57      reader = unibas_rgbd_reader()
58      rospy.init_node('unibas_rgbd_reader', anonymous=True)
59      try:
60          rospy.spin()
61      except KeyboardInterrupt:
62          print("Shutting down")
63          cv2.destroyAllWindows()
64
65  if __name__ == '__main__':
66      main(sys.argv)
```

creiamo unibas_visualizer.py

```
1  #!/usr/bin/env python
2  from __future__ import print_function
3
4  import roslib
5  roslib.load_manifest('unibas_viewer')
6  import sys
7  import rospy
8  import cv2
9  from std_msgs.msg import String
10 from sensor_msgs.msg import Image
11 from cv_bridge import CvBridge, CvBridgeError
12
13 class unibas_visualizer:
14
15     def __init__(self):
16         self.bridge = CvBridge()
17         self.image_sub = rospy.Subscriber("/unibas_viewer/rbgd", Image, self.callback)
18
```



creiamo unibas_visualizer.py

```
19  def callback(self,data):
20      try:
21          cv_image = self.bridge.imgmsg_to_cv2(data, "bgr8")
22      except CvBridgeError as e:
23          print(e)
24
25      cv2.imshow("rgbd", cv_image)
26      cv2.waitKey(30)
27
28
29 def main(args):
30     visualizer = unibas_visualizer()
31     rospy.init_node('unibas_viewer', anonymous=True)
32     try:
33         rospy.spin()
34     except KeyboardInterrupt:
35         print("Shutting down")
36         cv2.destroyAllWindows()
37
38 if __name__ == '__main__':
39     main(sys.argv)
```

permessi di esecuzione

Settiamo i permessi di esecuzione per i file

- unibas_rgbd_reader.py
- unibas_visualizer.py

con i comandi

```
chmod +x unibas_rgbd_reader.py
```

```
chmod +x unibas_visualizer.py
```

roscore

Apriamo un
primo
terminale e
lanciamo

roscore

roscore http://localhost:11311/

```
File Edit View Search Terminal Help
bloisi@bloisi-U36SG:~$ roscore
... logging to /home/bloisi/.ros/log/1e2e238e-7be0-11ea-af53-dc85de574b1d/roslaunch-bloisi-U36SG-26204.log
Checking log directory for disk usage. This may take a while.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://localhost:37155/
ros_comm version 1.14.5

SUMMARY
=====

PARAMETERS
* /rosdistro: melodic
* /rosversion: 1.14.5

NODES

auto-starting new master
process[master]: started with pid [26215]
ROS_MASTER_URI=http://localhost:11311

setting /run_id to 1e2e238e-7be0-11ea-af53-dc85de574b1d
process[rosout-1]: started with pid [26226]
started core service [/rosout]
```

rosrun

Apriamo un secondo terminale e lanciamo

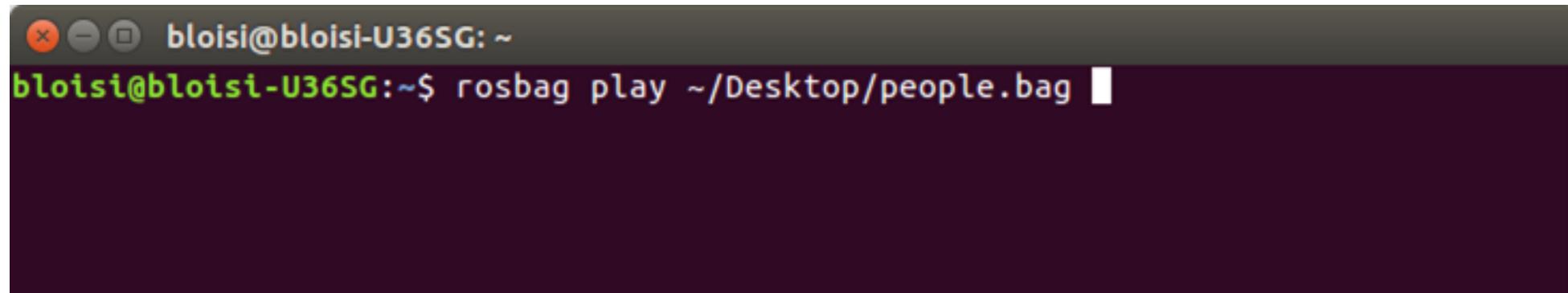
```
rosrun unibas_viewer unibas_rgbd_reader.py
```

rosbag play

Apriamo un terzo terminale e lanciamo

rosbag play <path-to-bag>

Per esempio:



```
bloisi@bloisi-U36SG: ~
bloisi@bloisi-U36SG:~$ rosbag play ~/Desktop/people.bag
```

A screenshot of a terminal window titled "bloisi@bloisi-U36SG: ~". The window contains a single command: "rosbag play ~/Desktop/people.bag". The terminal has a dark background with light-colored text.

rostopic list

Apriamo un quarto terminale e lanciamo

rostopic list

```
bloisi@bloisi-U36SG:~$ rostopic list
/camera/debayer/parameter_descriptions
/camera/debayer/parameter_updates
/camera/depth/image/compressed/parameter_descriptions
/camera/depth/image/compressed/parameter_updates
/camera/depth/image/compressedDepth/parameter_descriptions
/camera/depth/image/compressedDepth/parameter_updates
/camera/depth/image/theora/parameter_descriptions
/camera/depth/image/theora/parameter_updates
/camera/depth/image_raw/compressed/parameter_descriptions
/camera/depth/image_raw/compressed/parameter_updates
/camera/depth/image_raw/compressedDepth/parameter_descriptions
/camera/depth/image_raw/compressedDepth/parameter_updates
/camera/depth/image_raw/theora/parameter_descriptions
/camera/depth/image_raw/theora/parameter_updates
/camera/depth/image_rect/compressed/parameter_descriptions
/camera/depth/image_rect/compressed/parameter_updates
/camera/depth/image_rect/compressedDepth/parameter_descriptions
/camera/depth/image_rect/compressedDepth/parameter_updates
/camera/depth/image_rect/theora/parameter_descriptions
/camera/depth/image_rect/theora/parameter_updates
/camera/depth/image_rect_raw/compressed/parameter_descriptions
/camera/depth/image_rect_raw/compressed/parameter_updates
/camera/depth/image_rect_raw/compressedDepth/parameter_descriptions
/camera/depth/image_rect_raw/compressedDepth/parameter_updates
/camera/depth/image_rect_raw/theora/parameter_descriptions
/camera/depth/image_rect_raw/theora/parameter_updates
/camera/depth_rectify_depth/parameter_descriptions
/camera/depth_rectify_depth/parameter_updates
/camera/depth_registered/camera_info
/camera/depth_registered/disparity
/camera/depth_registered/hw_registered/image_rect_raw
/camera/depth_registered/hw_registered/image_rect_raw/compressed
/camera/depth_registered/hw_registered/image_rect_raw/compressed/parameter_descriptions
/camera/depth_registered/hw_registered/image_rect_raw/compressed/parameter_updates
/camera/depth_registered/hw_registered/image_rect_raw/compressedDepth
/camera/depth_registered/hw_registered/image_rect_raw/compressedDepth/parameter_descriptions
/camera/depth_registered/hw_registered/image_rect_raw/compressedDepth/parameter_updates
/camera/depth_registered/hw_registered/image_rect_raw/theora
```

rostopic list

```
bloisi@bloisi-U36SG: ~
/camera/depth_registered/hw_registered/image_rect_raw/theora/parameter_descriptions
/camera/depth_registered/hw_registered/image_rect_raw/theora/parameter_updates
/camera/depth_registered/image_raw
/camera/depth_registered/image_raw/compressed
/camera/depth_registered/image_raw/compressed/parameter_descriptions
/camera/depth_registered/image_raw/compressed/parameter_updates
/camera/depth_registered/image_raw/compressedDepth
/camera/depth_registered/image_raw/compressedDepth/parameter_descriptions
/camera/depth_registered/image_raw/compressedDepth/parameter_updates
/camera/depth_registered/image_raw/theora
/camera/depth_registered/image_raw/theora/parameter_descriptions
/camera/depth_registered/image_raw/theora/parameter_updates
/camera/depth_registered/points
/camera/depth_registered/sw_registered/image_rect_raw/compressed/parameter_descriptions
/camera/depth_registered/sw_registered/image_rect_raw/compressed/parameter_updates
/camera/depth_registered/sw_registered/image_rect_raw/compressedDepth/parameter_descriptions
/camera/depth_registered/sw_registered/image_rect_raw/compressedDepth/parameter_updates
/camera/depth_registered/sw_registered/image_rect_raw/theora/parameter_descriptions
/camera/depth_registered/sw_registered/image_rect_raw/theora/parameter_updates
/camera/depth_registered_rectify_depth/parameter_descriptions
/camera/depth_registered_rectify_depth/parameter_updates
/camera/driver/parameter_descriptions
/camera/driver/parameter_updates
/camera/ir/image_raw/compressed/parameter_descriptions
/camera/ir/image_raw/compressed/parameter_updates
/camera/ir/image_raw/compressedDepth/parameter_descriptions
/camera/ir/image_raw/compressedDepth/parameter_updates
/camera/ir/image_raw/theora/parameter_descriptions
/camera/ir/image_raw/theora/parameter_updates
/camera/ir/image_rect_ir/compressed/parameter_descriptions
/camera/ir/image_rect_ir/compressed/parameter_updates
/camera/ir/image_rect_ir/compressedDepth/parameter_descriptions
/camera/ir/image_rect_ir/compressedDepth/parameter_updates
/camera/ir/image_rect_ir/theora/parameter_descriptions
/camera/ir/image_rect_ir/theora/parameter_updates
/camera/projector/camera_info
/camera/rectify_color/parameter_descriptions
/camera/rectify_color/parameter_updates
/camera/rectify_ir/parameter_descriptions
```

rostopic list

```
bloisi@bloisi-U36SG: ~
/camera/rgb/image_color/theora/parameter_updates
/camera/rgb/image_mono
/camera/rgb/image_mono/compressed
/camera/rgb/image_mono/compressed/parameter_descriptions
/camera/rgb/image_mono/compressed/parameter_updates
/camera/rgb/image_mono/compressedDepth/parameter_descriptions
/camera/rgb/image_mono/compressedDepth/parameter_updates
/camera/rgb/image_mono/theora
/camera/rgb/image_mono/theora/parameter_descriptions
/camera/rgb/image_mono/theora/parameter_updates
/camera/rgb/image_raw
/camera/rgb/image_raw/compressed
/camera/rgb/image_raw/compressed/parameter_descriptions
/camera/rgb/image_raw/compressed/parameter_updates
/camera/rgb/image_raw/compressedDepth/parameter_descriptions
/camera/rgb/image_raw/compressedDepth/parameter_updates
/camera/rgb/image_raw/theora
/camera/rgb/image_raw/theora/parameter_descriptions
/camera/rgb/image_raw/theora/parameter_updates
/camera/rgb/image_rect_color
/camera/rgb/image_rect_color/compressed
/camera/rgb/image_rect_color/compressed/parameter_descriptions
/camera/rgb/image_rect_color/compressed/parameter_updates
/camera/rgb/image_rect_color/compressedDepth/parameter_descriptions
/camera/rgb/image_rect_color/compressedDepth/parameter_updates
/camera/rgb/image_rect_color/theora
/camera/rgb/image_rect_color/theora/parameter_descriptions
/camera/rgb/image_rect_color/theora/parameter_updates
/camera/rgb/image_rect_mono
/camera/rgb/image_rect_mono/compressed
/camera/rgb/image_rect_mono/compressed/parameter_descriptions
/camera/rgb/image_rect_mono/compressed/parameter_updates
/camera/rgb/image_rect_mono/compressedDepth/parameter_descriptions
/camera/rgb/image_rect_mono/compressedDepth/parameter_updates
/camera/rgb/image_rect_mono/theora
/camera/rgb/image_rect_mono/theora/parameter_descriptions
/camera/rgb/image_rect_mono/theora/parameter_updates
/clock
```

visualizzazione

Apriamo un quinto terminale e lanciamo

```
rosrun unibas_viewer unibas_visualizer.py
```



repository unibas_viewer

unibas_viewer

ROS package for reading RGBD data

This code is part of the material of the course [Computer Vision and Machine Perception](#) - University of Basilicata (Italy)

This code is provided without any warranty about its usability. It is for educational purposes and should be regarded as such.



https://github.com/dbloisi/unibas_viewer



**UNIVERSITÀ DEGLI STUDI
DELLA BASILICATA**

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Docente
Domenico Daniele Bloisi

ROS+OpenCV

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