

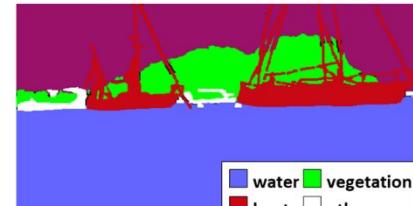
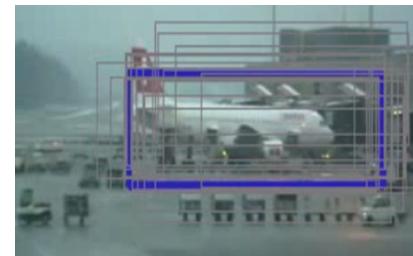
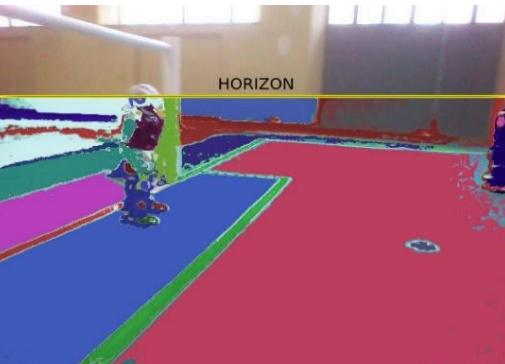


**UNIVERSITÀ DEGLI STUDI  
DELLA BASILICATA**

# *Corso di Visione e Percezione*

Docente  
**Domenico D. Bloisi**

# ROS+OpenCV



# Domenico Daniele Bloisi

---

- Ricercatore RTD B

Dipartimento di Matematica, Informatica  
ed Economia

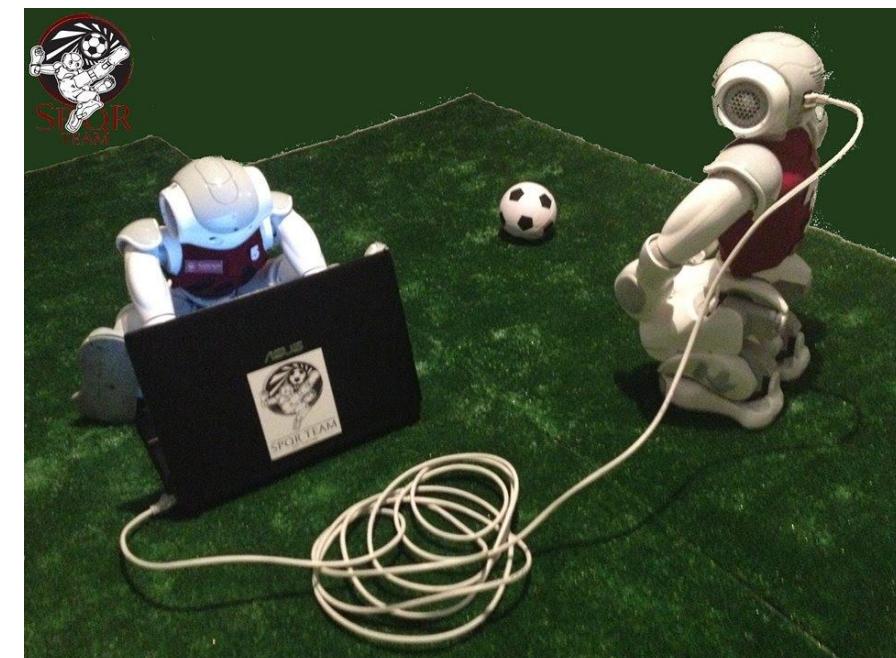
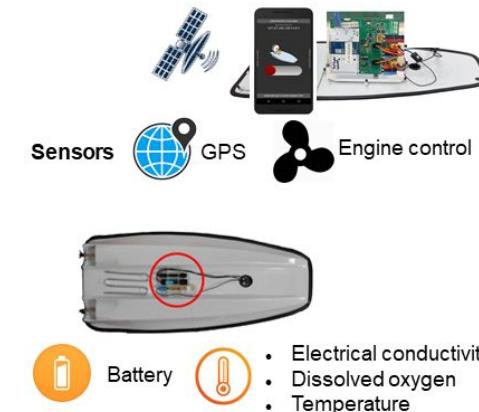
Università degli studi della Basilicata

<http://web.unibas.it/bloisi>

- SPQR Robot Soccer Team

Dipartimento di Informatica, Automatica  
e Gestionale Università degli studi di  
Roma “La Sapienza”

<http://spqr.diag.uniroma1.it>



# Informazioni sul corso

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- Home page del corso  
<http://web.unibas.it/bloisi/corsi/visione-e-percezione.html>
- Docente: Domenico Daniele Bloisi
- Periodo: **Il semestre** marzo 2021 – giugno 2021

Martedì 17:00-19:00 (Aula COPERNICO)

Mercoledì 8:30-10:30 (Aula COPERNICO)



Codice corso Google Classroom:  
<https://classroom.google.com/c/Njl2MjA4MzgzNDFa?cjc=xgolays>

# Ricevimento

---

- Su appuntamento tramite Google Meet

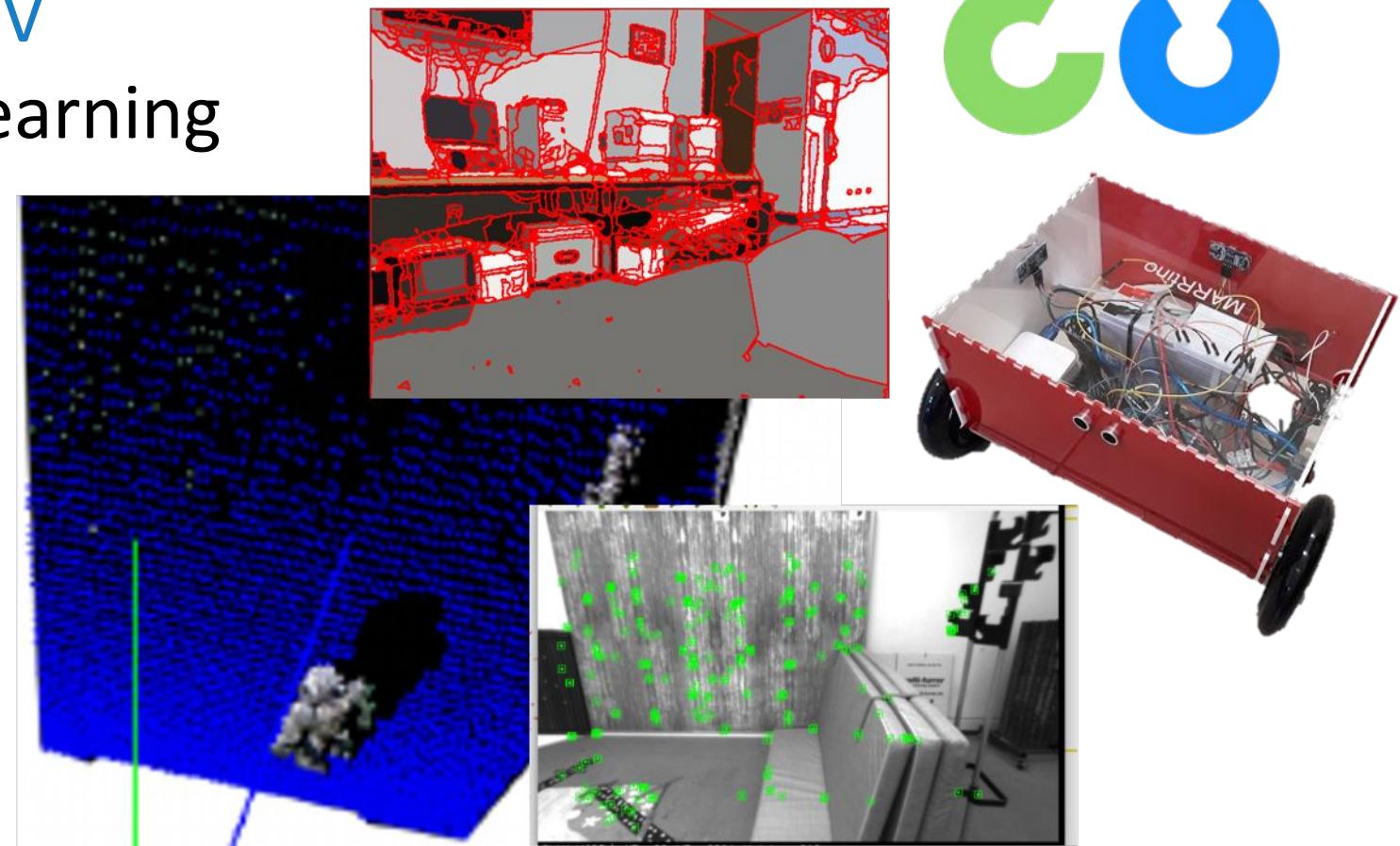
Per prenotare un appuntamento inviare  
una email a  
[domenico.bloisi@unibas.it](mailto:domenico.bloisi@unibas.it)



# Programma – Visione e Percezione

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- Introduzione al linguaggio Python
- Elaborazione delle immagini con Python
- [Percezione 2D – OpenCV](#)
- Introduzione al Deep Learning
- [ROS](#)
- Il paradigma publisher and subscriber
- Simulatori
- Percezione 3D - PCL



# 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  
primo 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

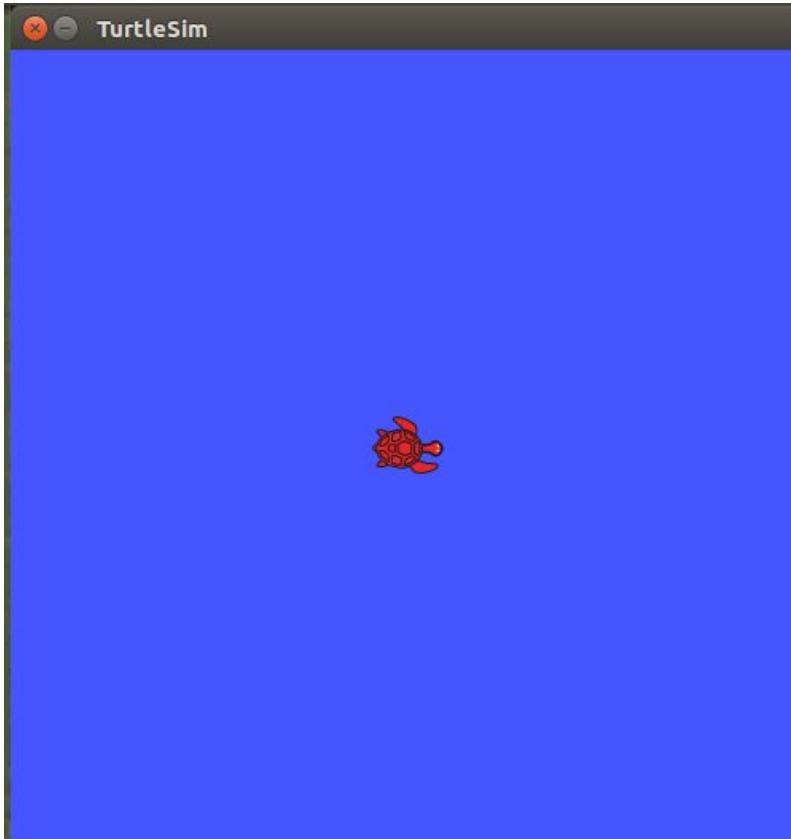
auto-starting new master
process[master]: started with pid [2523]
ROS_MASTER_URI=http://localhost:11311/

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



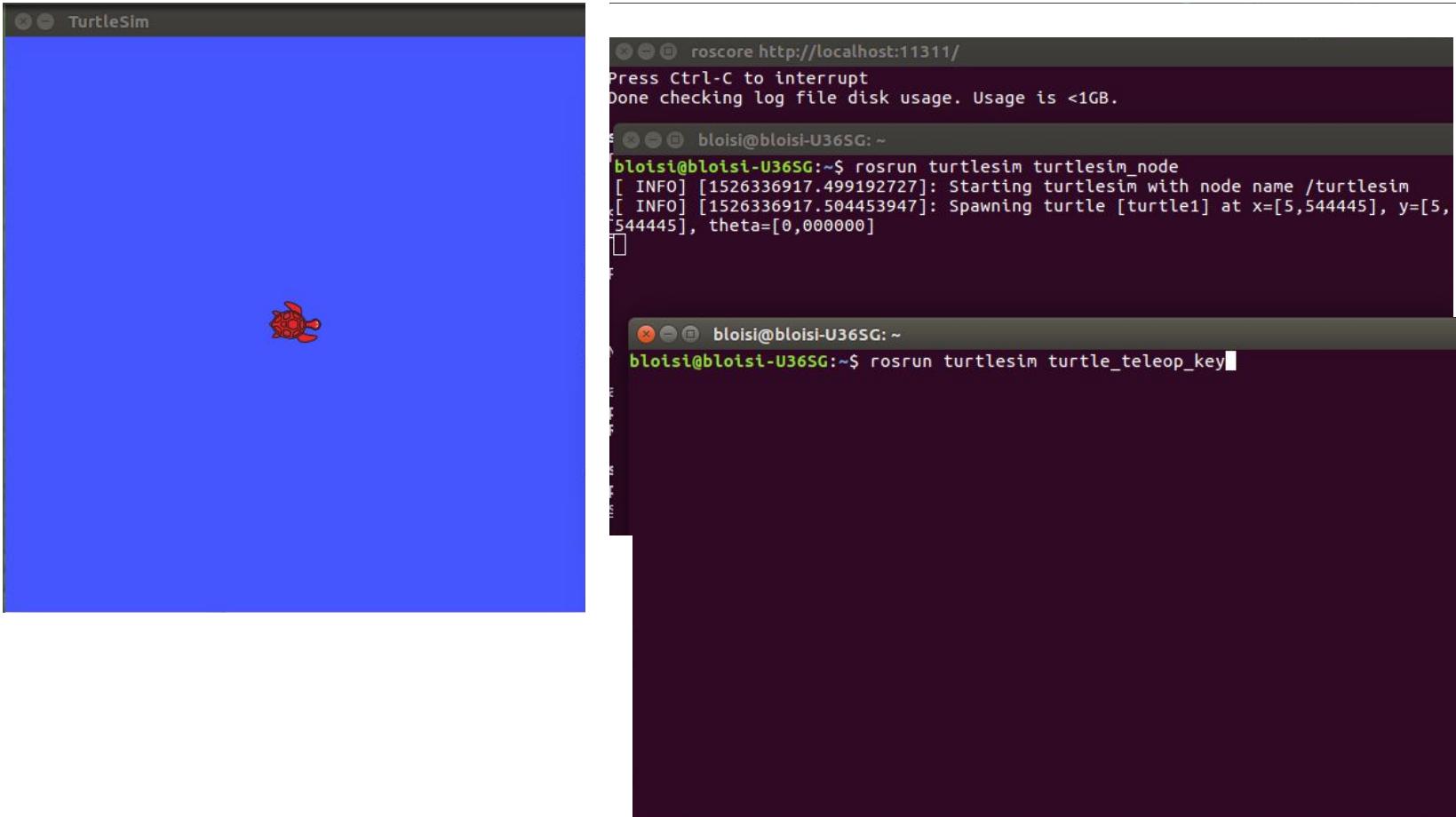
```
bloisi@bloisi-U36SG:~$ rosrun turtlesim turtlesim_node
[ INFO] [1526336917.499192727]: Starting turtlesim with node name /turtlesim
[ INFO] [1526336917.504453947]: Spawning turtle [turtle1] at x=[5,544445], y=[5,544445], theta=[0,000000]
```

# Esempio rosbag - teleop

---

Apriamo un **terzo terminal** e digitiamo

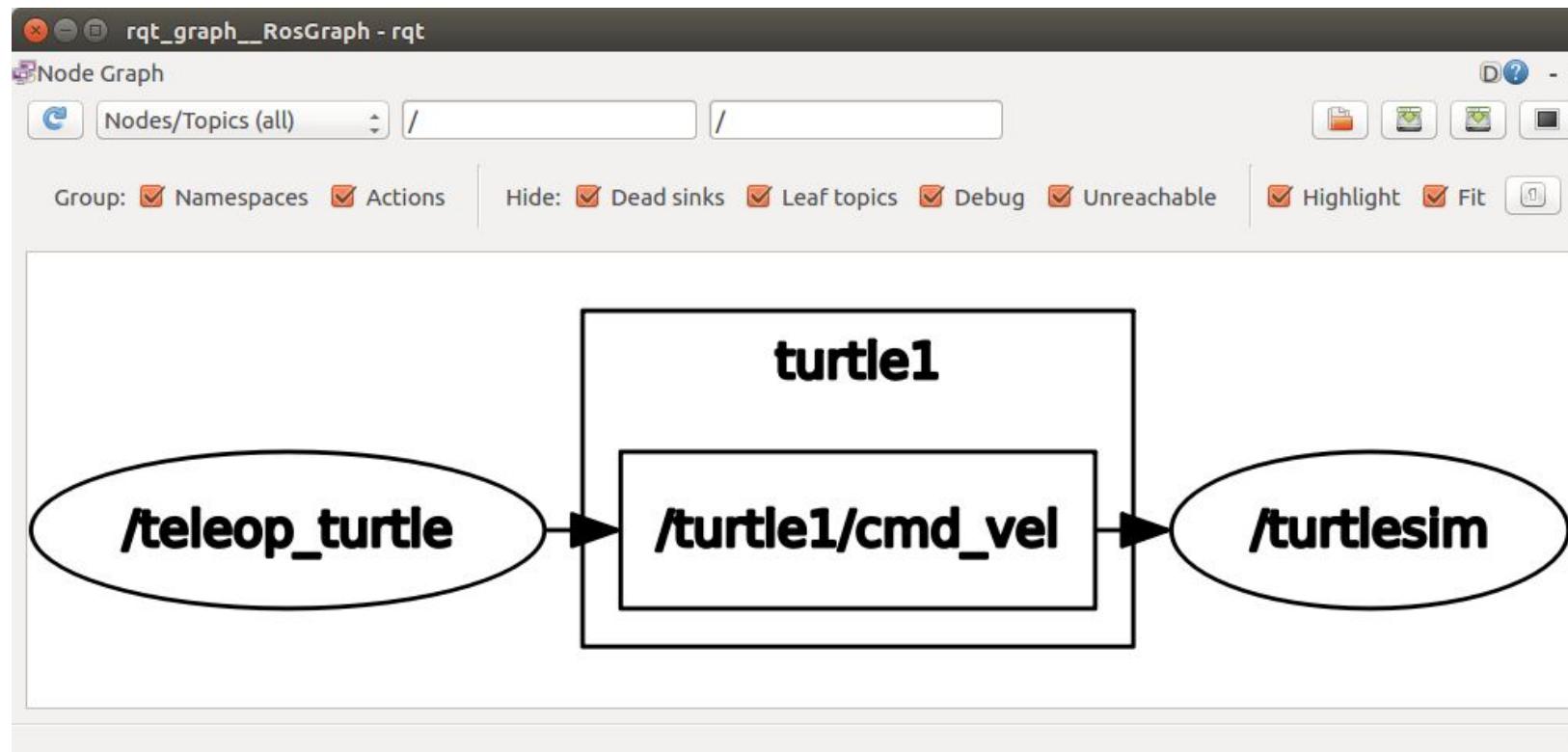
`rosrun turtlesim turtle_teleop_key`



# rqt\_graph

---

Apriamo un **quarto terminal** e digitiamo  
rqt\_graph  
per verificare che i due nodi siano in collegamento tra loro

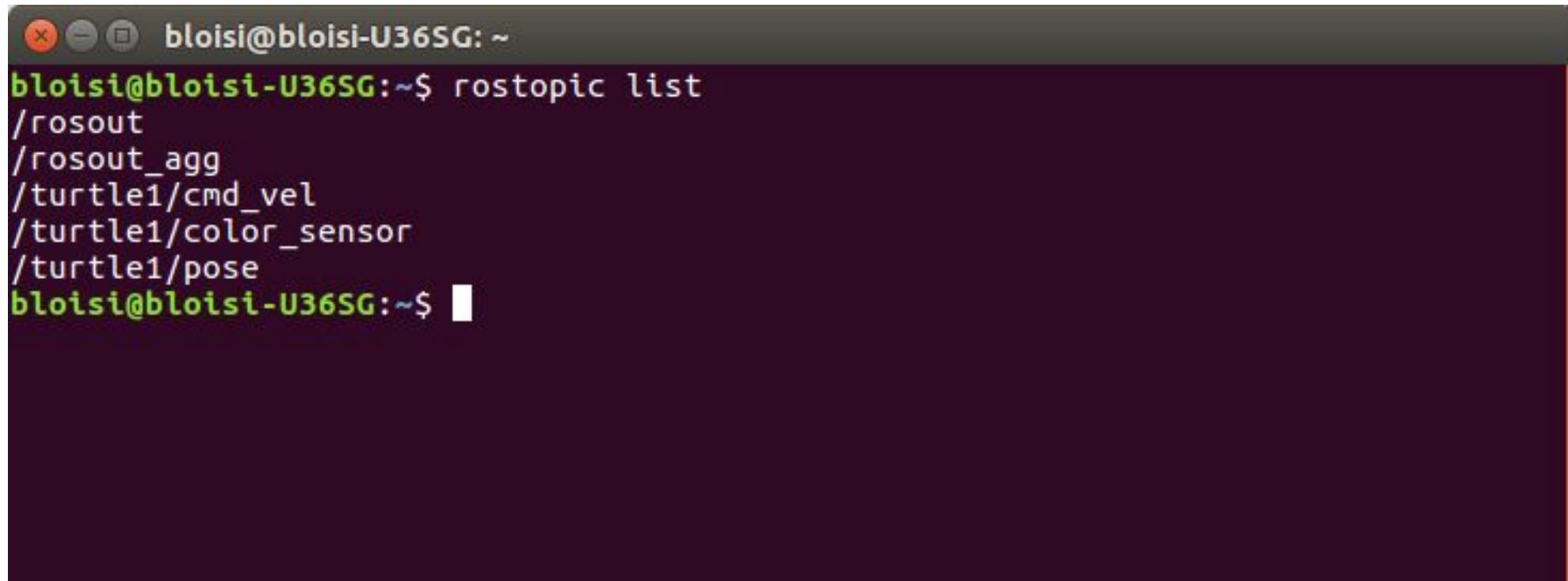


# rostopic

---

Controlliamo anche la 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 useremo

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

# Esempio - Registrare un topic



```
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: ~$ rosrund turtlesim turtle_teleop_key
Reading from keyboard
-----
Use arrow keys to move the turtle.

bloisi@bloisi-U36SG: ~$ rostopic list
/roslaunch
/roslaunch_agg
/turtle1/cmd_vel
/turtle1/color_sensor
/turtle1/pose
bloisi@bloisi-U36SG: ~$ rosbag record /turtle1/cmd_vel
```

# 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=[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

---

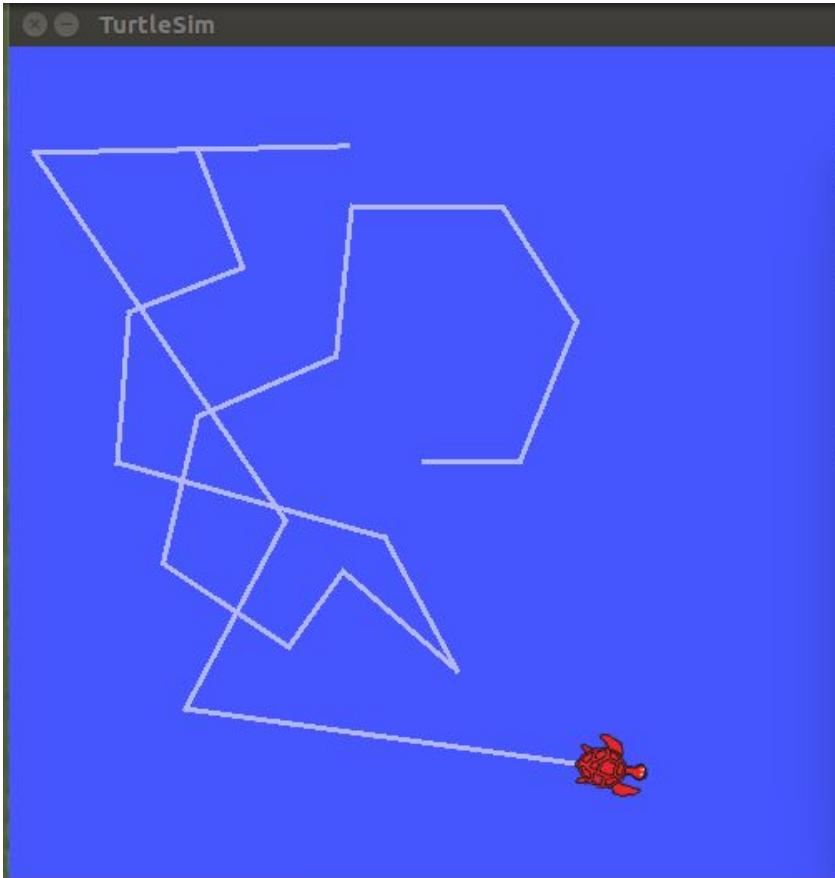
Se si vogliono registrare tutti i topic attivi, si può usare l'opzione -a

```
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:~$
```

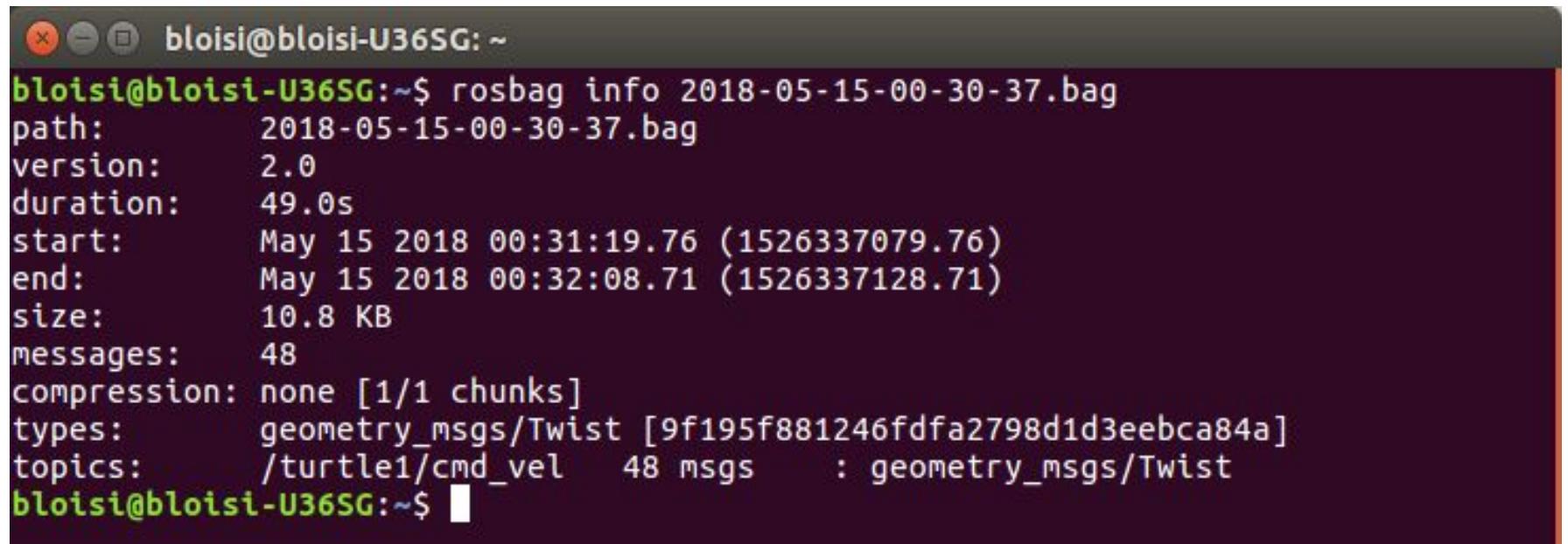
A terminal window showing a Linux command-line interface. The prompt is "bloisi@bloisi-U36SG:~\$". The user runs the command "rostopic list" which outputs a list of ROS topics: "/rosout", "/rosout\_agg", "/turtle1/cmd\_vel", "/turtle1/color\_sensor", and "/turtle1/pose". Then, the user runs "rosbag record /turtle1/cmd\_vel" which subscribes to the "/turtle1/cmd\_vel" topic and starts recording data to a file named "2018-05-15-00-30-37.bag". Finally, the user presses Ctrl-C to terminate the recording process.

# 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>
```

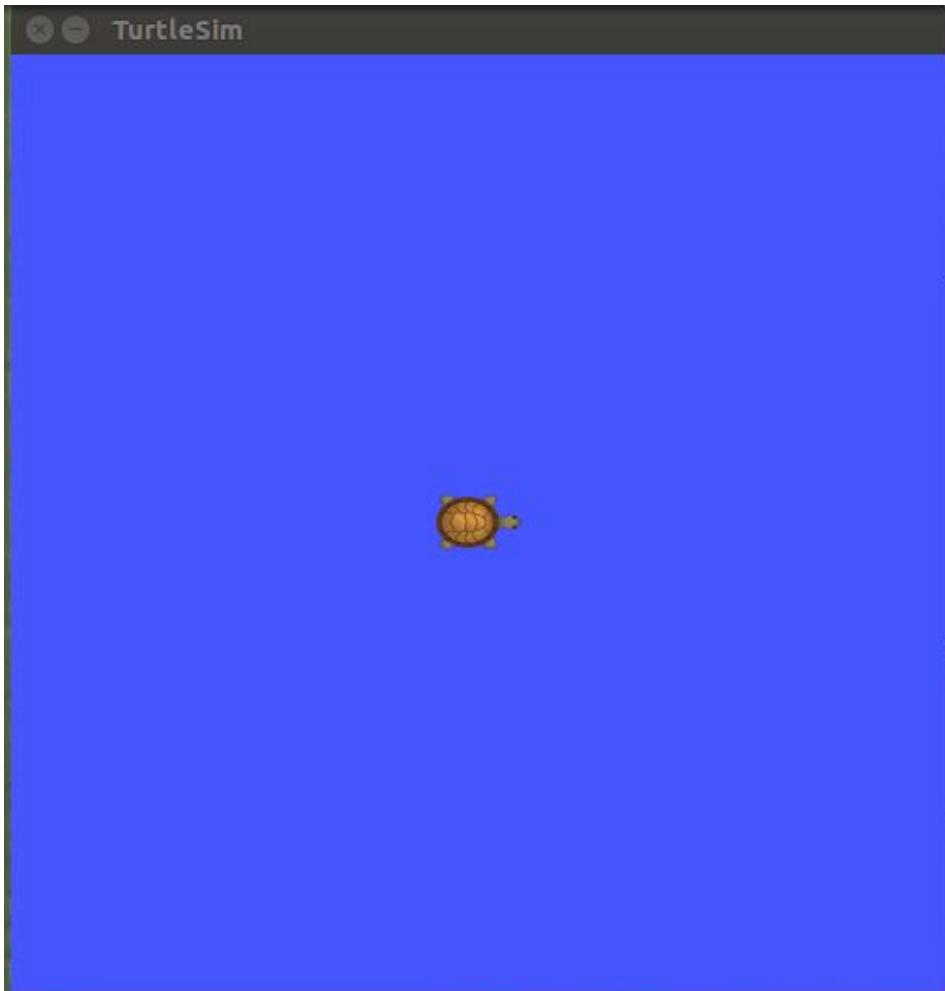
Per riprodurre la bag 2018-05-15-00-30-37.bag:

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
```

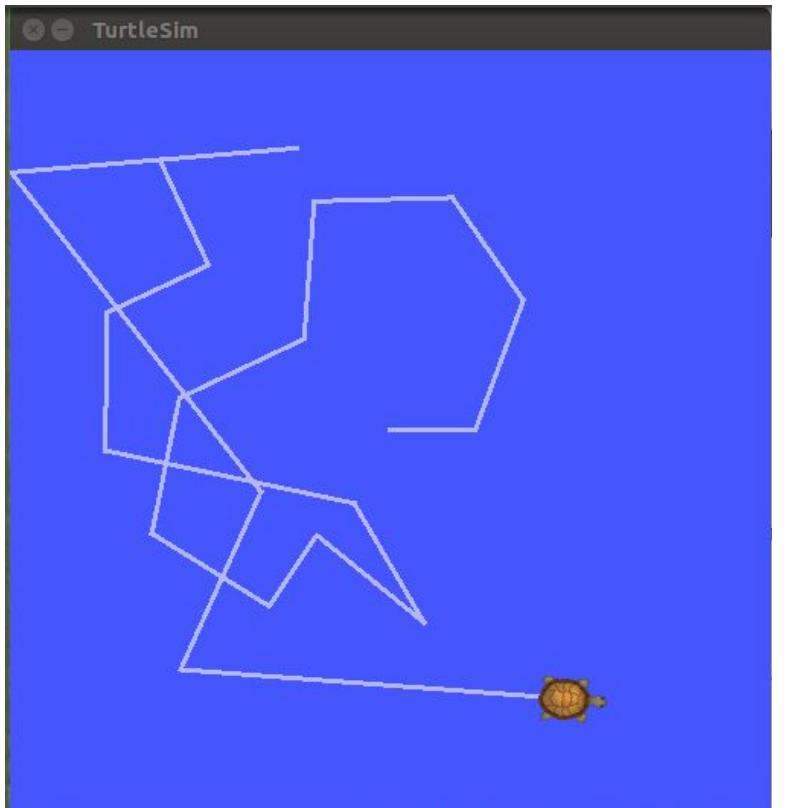
# rosbag play – esecuzione in corso



```
bloisi@bloisi-U36SG:~$ rosrun turtlesim turtlesim_node
[ INFO] [1526336917.49919272]: Starting turtlesim with node name /turtlesim
[ INFO] [1526336917.50445394]: Spawning turtle [turtle1] at x=[5,544445], y=[5,544445], theta=[0,000000]
^C
bloisi@bloisi-U36SG:~$ rosrun turtlesim turtlesim_node
[ INFO] [1526337414.14620863]: Starting turtlesim with node name /turtlesim
[ INFO] [1526337414.15195380]: Spawning turtle [turtle1] at x=[5,544445], y=[5,544445], theta=[0,000000]

[ RUNNING] Bag Time: 1526337090.591895 Duration: 10.836131 / 48.957648
[ RUNNING] Bag Time: 1526337090.692036 Duration: 10.936272 / 48.957648
[ RUNNING] Bag Time: 1526337090.791511 Duration: 11.035747 / 48.957648
[ RUNNING] Bag Time: 1526337090.891664 Duration: 11.135900 / 48.957648
[ RUNNING] Bag Time: 1526337090.991832 Duration: 11.236068 / 48.957648
[ RUNNING] Bag Time: 1526337091.091962 Duration: 11.336197 / 48.957648
[ RUNNING] Bag Time: 1526337091.192129 Duration: 11.436365 / 48.957648
[ RUNNING] Bag Time: 1526337091.248360 Duration: 11.492596 / 48.957648
[ RUNNING] Bag Time: 1526337091.348569 Duration: 11.592805 / 48.957648
[ RUNNING] Bag Time: 1526337091.448749 Duration: 11.692984 / 48.957648
[ RUNNING] Bag Time: 1526337091.548924 Duration: 11.793160 / 48.957648
[ RUNNING] Bag Time: 1526337091.649109 Duration: 11.893345 / 48.957648
[ RUNNING] Bag Time: 1526337091.749240 Duration: 11.993475 / 48.957648
[ RUNNING] Bag Time: 1526337091.849477 Duration: 12.093713 / 48.957648
[ RUNNING] Bag Time: 1526337091.949632 Duration: 12.193868 / 48.957648
[ RUNNING] Bag Time: 1526337092.049816 Duration: 12.294051 / 48.957648
[ RUNNING] Bag Time: 1526337092.150008 Duration: 12.394243 / 48.957648
[ RUNNING] Bag Time: 1526337092.250157 Duration: 12.494392 / 48.957648
[ RUNNING] Bag Time: 1526337092.312010 Duration: 12.556246 / 48.957648
[ RUNNING] Bag Time: 1526337092.412182 Duration: 12.656418 / 48.957648
[ RUNNING] Bag Time: 1526337092.512428 Duration: 12.756664 / 48.957648
[ RUNNING] Bag Time: 1526337092.612576 Duration: 12.856811 / 48.957648
[ RUNNING] Bag Time: 1526337092.712744 Duration: 12.956980 / 48.957648
```

# rosbag play – risultato finale



```
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=[0,00000]
^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=[0,00000]
[ ]
```

```
[ ]
```

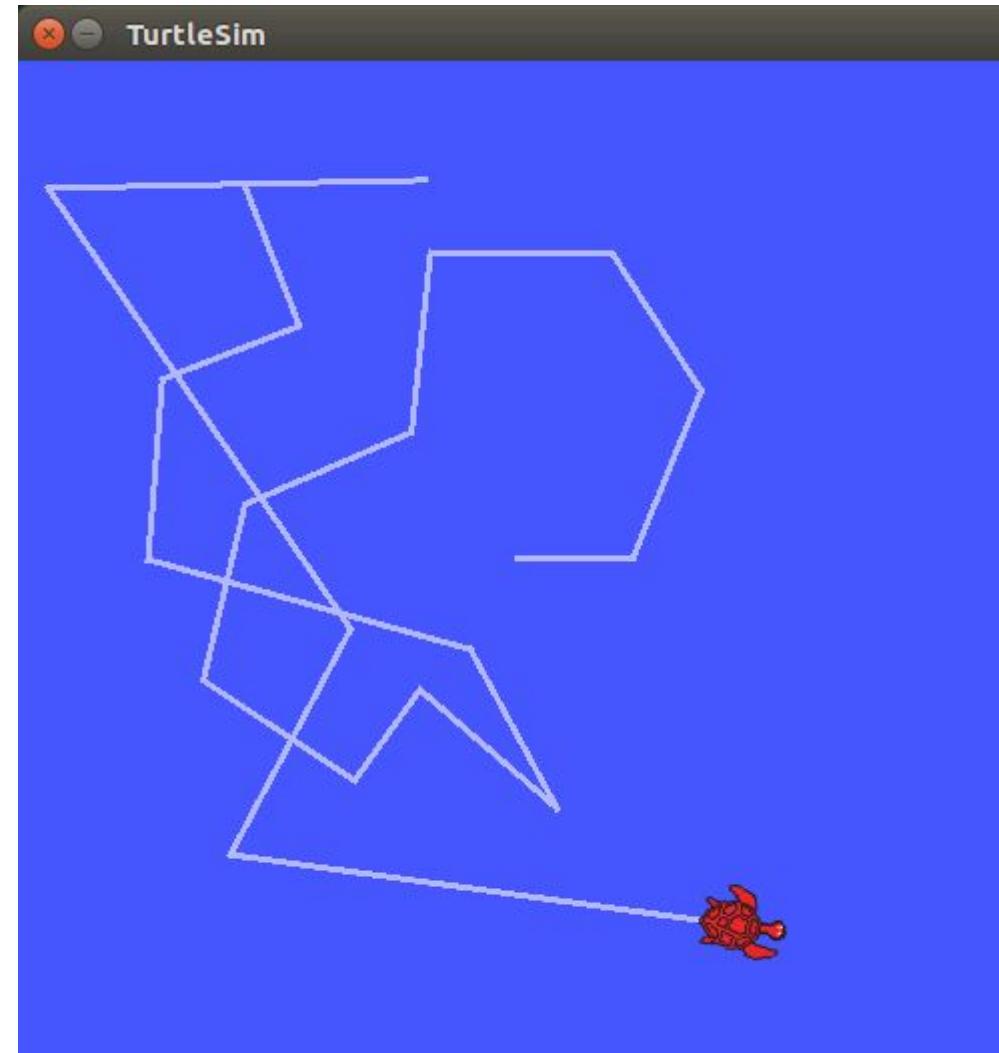
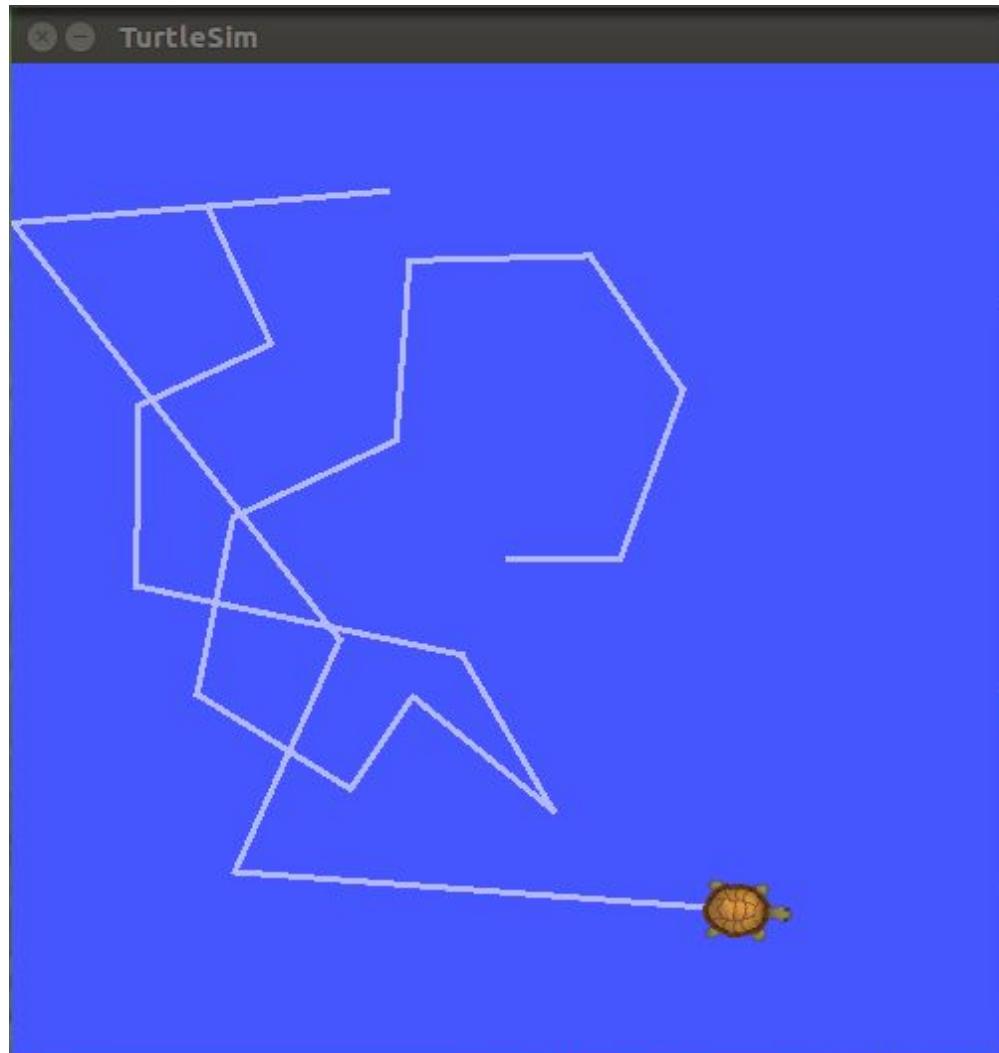
```
bloisi@bloisi-U36SG: ~
[RUNNING] Bag Time: 1526337126.557608 Duration: 46.801843 / 48.957648
[RUNNING] Bag Time: 1526337126.657763 Duration: 46.901998 / 48.957648
[RUNNING] Bag Time: 1526337126.757943 Duration: 47.002178 / 48.957648
[RUNNING] Bag Time: 1526337126.858106 Duration: 47.102342 / 48.957648
[RUNNING] Bag Time: 1526337126.958296 Duration: 47.202532 / 48.957648
[RUNNING] Bag Time: 1526337127.058506 Duration: 47.302742 / 48.957648
[RUNNING] Bag Time: 1526337127.158664 Duration: 47.402900 / 48.957648
[RUNNING] Bag Time: 1526337127.258812 Duration: 47.503048 / 48.957648
[RUNNING] Bag Time: 1526337127.358996 Duration: 47.603232 / 48.957648
[RUNNING] Bag Time: 1526337127.459208 Duration: 47.703444 / 48.957648
[RUNNING] Bag Time: 1526337127.559368 Duration: 47.803604 / 48.957648
[RUNNING] Bag Time: 1526337127.659556 Duration: 47.903791 / 48.957648
[RUNNING] Bag Time: 1526337127.759781 Duration: 48.004016 / 48.957648
[RUNNING] Bag Time: 1526337127.857417 Duration: 48.101653 / 48.957648
[RUNNING] Bag Time: 1526337127.957637 Duration: 48.201872 / 48.957648
[RUNNING] Bag Time: 1526337128.057879 Duration: 48.302115 / 48.957648
[RUNNING] Bag Time: 1526337128.158112 Duration: 48.402348 / 48.957648
[RUNNING] Bag Time: 1526337128.258319 Duration: 48.502555 / 48.957648
[RUNNING] Bag Time: 1526337128.358572 Duration: 48.602807 / 48.957648
[RUNNING] Bag Time: 1526337128.458740 Duration: 48.702976 / 48.957648
[RUNNING] Bag Time: 1526337128.558883 Duration: 48.803119 / 48.957648
```

Done.

```
bloisi@bloisi-U36SG:~$
```

# 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](https://drive.google.com/file/d/1F8pd_Cc5n67cMkWdvTZphpi7zeCRJDEJ/view?usp=sharing)

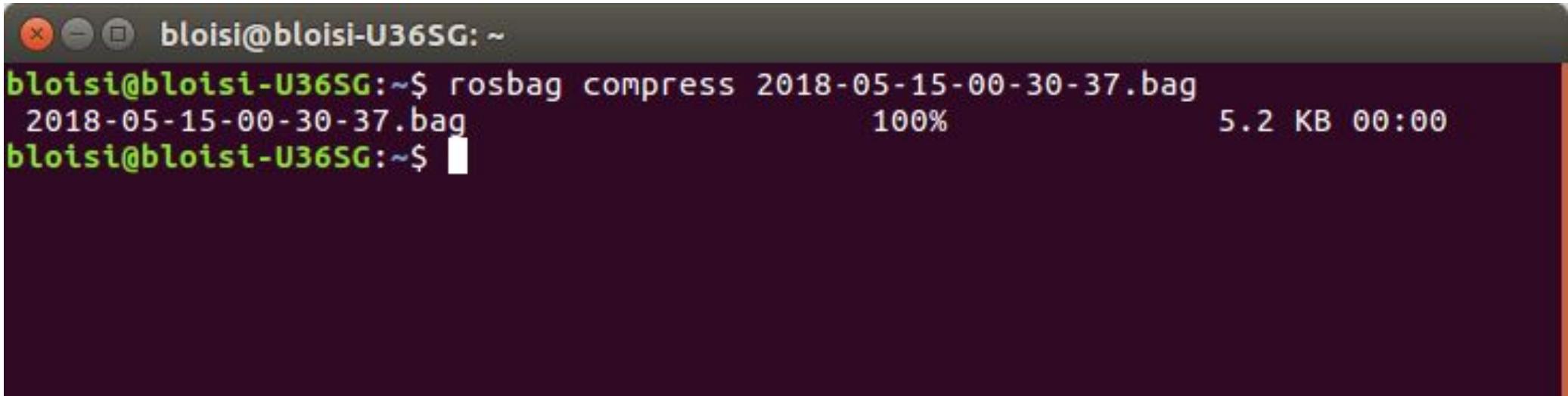
# rosbag compress

---

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 title bar reads "bloisi@bloisi-U36SG: ~". The command "rosbag compress 2018-05-15-00-30-37.bag" is entered at the prompt. The output shows the progress: "100%" completion, "5.2 KB" size, and "00:00" duration. The terminal ends with a "\$" prompt.

```
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:~$
```

# rosbag compress – esecuzione

---

```
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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## cv\_bridge

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## 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](https://github.com/ros-perception/vision_opencv/issues)
- Source: git [https://github.com/ros-perception/vision\\_opencv.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 \(10\)](#)

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[RecentChanges](#)  
[cv\\_bridge](#)

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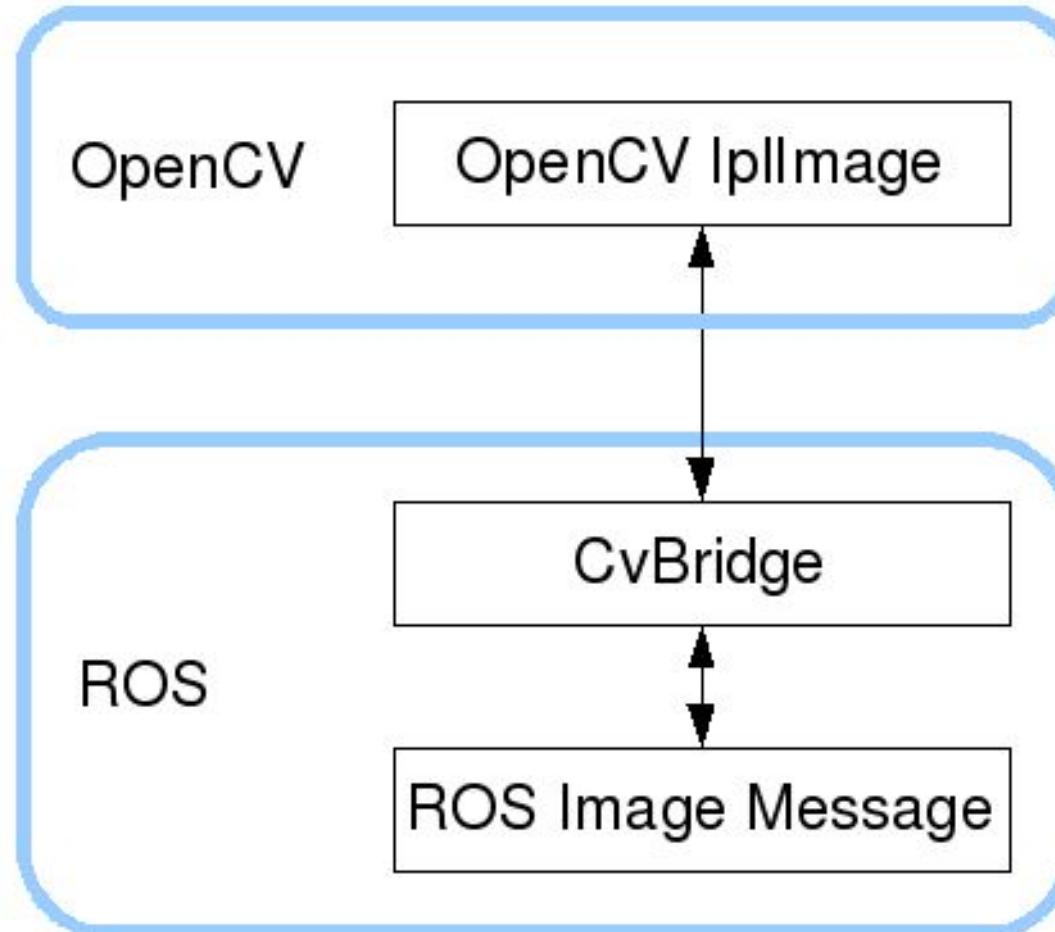
Altre azioni: ▾

Utente

Accedi

# cv\_bridge

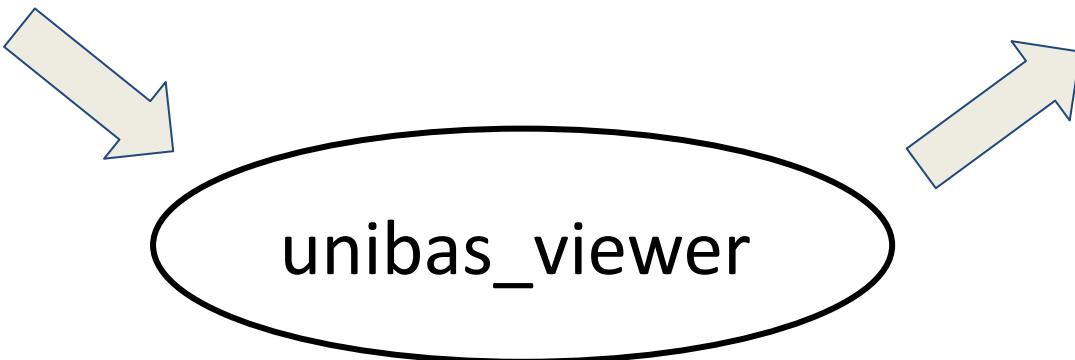
---



# Esempio: unibas\_viewer

---

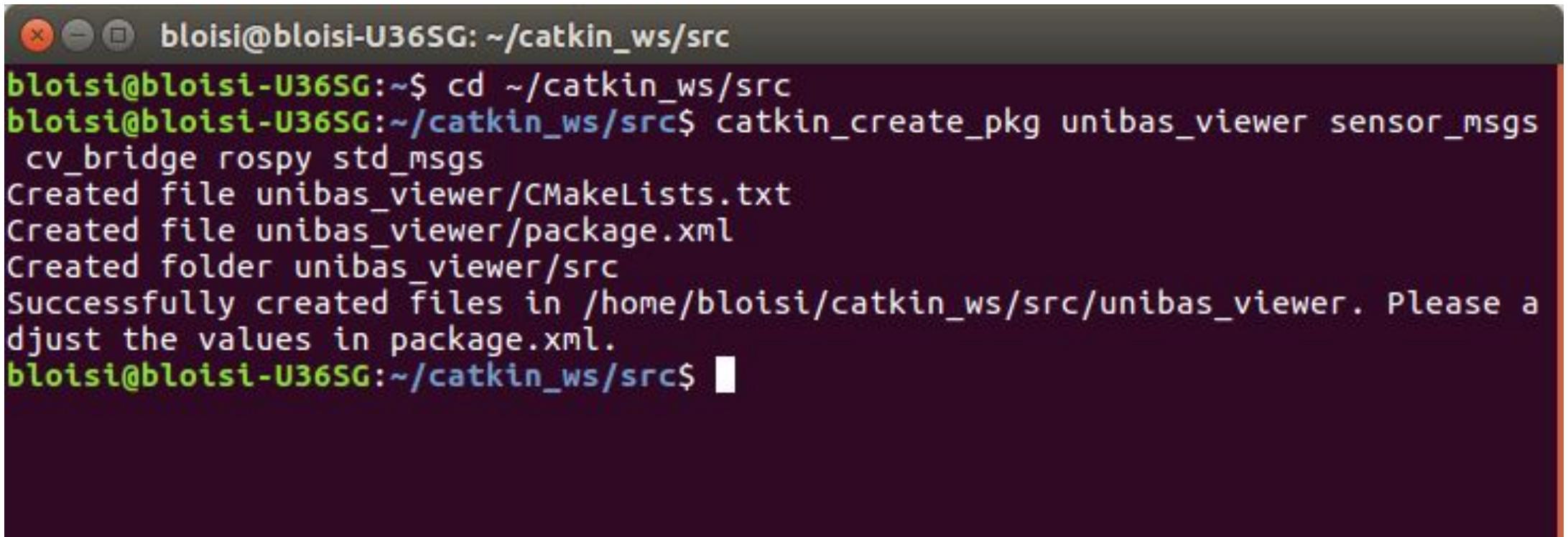
rosbag acquisita con  
un sensore RGBD



visualizzazione dati  
color + depth  
con OpenCV

# creazione del nodo unibas\_viewer

---



```
bloisi@bloisi-U36SG: ~/catkin_ws/src
bloisi@bloisi-U36SG:~$ 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

---



[http://wiki.ros.org/cv\\_bridge/Tutorials/ConvertingBetweenROSImagesAndOpenCVImagesPython](http://wiki.ros.org/cv_bridge/Tutorials/ConvertingBetweenROSImagesAndOpenCVImagesPython)

# 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

```
bloisi@bloisi-U36SG: ~/catkin_ws
[ 52%] Built target hw1_generate_messages_py
[ 53%] Built target hw1_generate_messages_lisp
. ~/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$
```

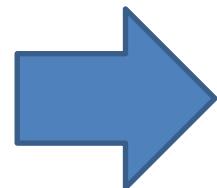
# rospack find

```
bloisi@bloisi-U36SG: ~/catkin_ws
[ 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_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$ 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:
```

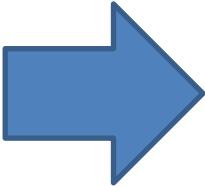
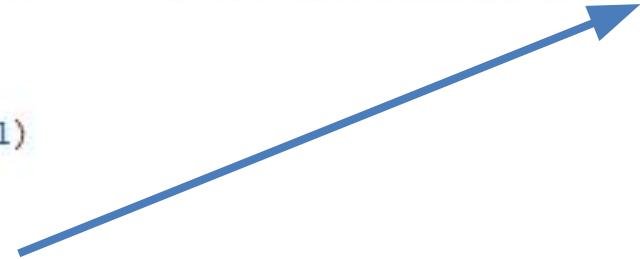


# Creiamo unibas\_rgbd\_reader.py

---

```
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
```

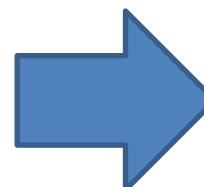
the slop parameter defines the delay (in seconds) with which messages can be synchronized



# Creiamo unibas\_rgbd\_reader.py

---

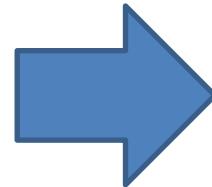
```
26     def callback(self, rgb_data, depth_data):  
27  
28         try:  
29             cv_image = self.bridge.imgmsg_to_cv2(rgb_data, "bgr8")  
30             depth_image = self.bridge.imgmsg_to_cv2(depth_data, "32FC1")  
31             depth_array = np.array(depth_image, dtype=np.float32)  
32             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

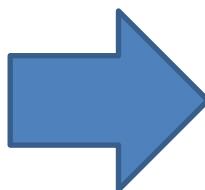
---

```
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 terminal  
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 terminal** e lanciamo

```
rosrun unibas_viewer unibas_rgbd_reader.py
```

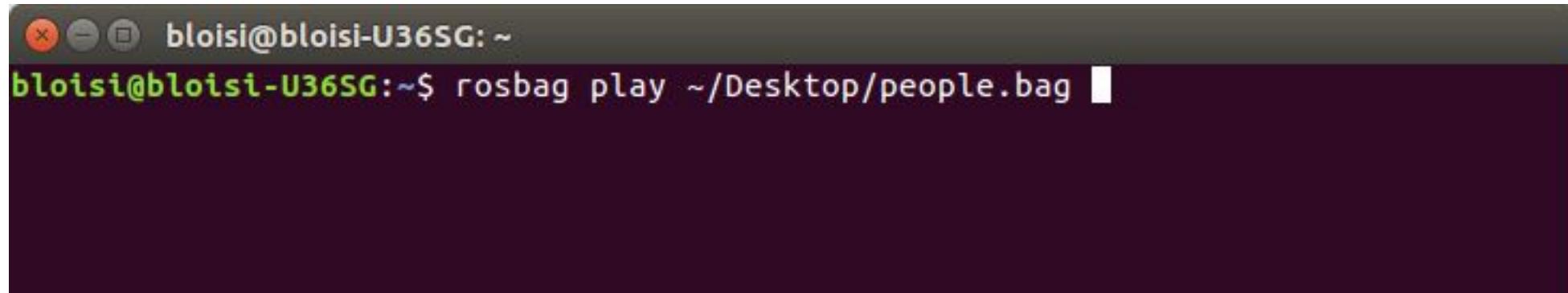
# rosbag play

---

Apriamo un **terzo terminal** e lanciamo

`rosbag play <path-to-bag>`

Per esempio:



A screenshot of a terminal window titled "bloisi@bloisi-U36SG: ~". The window contains a single line of text: "bloisi@bloisi-U36SG:~\$ rosbag play ~/Desktop/people.bag". The terminal has a dark background with light-colored text and standard window controls at the top.

# rostopic list

---

Apriamo un quarto terminal 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

---

continua...

```
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

---

Abbiamo tantissimi  
topic!

```
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 terminal** 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](https://github.com/dbloisi/unibas_viewer)



**UNIVERSITÀ DEGLI STUDI  
DELLA BASILICATA**

# *Corso di Visione e Percezione*



Docente  
**Domenico D. Bloisi**

# ROS+OpenCV

