ROS NOTES

version 2/12/2020

Run existing nodes

0. Make sure the catkin setup has been sourced.

```
$  echo  $ROS_PACKAGE_PATH     #should give something like
>> /home/tm/catkin_ws/src:/opt/ros/kinetic/share
```

**if your catkin_ws is missing, source the catkin setup. This will need to be done in each terminal unless you've done it permanently. Highly recommend doing it permanently.

Permanent catkin source

-open ~/.bashrc in a text editor
-find `source /opt/ros/[distro]/setup.bash`
-under that add `source ~/yourPathTo/catkin_ws/devel/setup.bash`
`-save`

Catkin source in each terminal

$ source ~/catkin_ws/devel/setup.bash

1. Start ROS
   $ roscore
2. Run node in new terminal
   $ rosrun [package_name] [node_name] or, list with $ rosrun [package_name] <tab><tab>
   – optional- can rename node like
   $ rosrun [package_name] [node_name] __name:=my_name
3. Run as many nodes as needed in new terminals

OR

1. Start ROS
   $ roscore
2. roslaunch to do a defined setup
   $ roslaunch [package] [filename.launch]
   -to set up the launch file, see http://wiki.ros.org/ROS/Tutorials/UsingRqtconsoleRoslaunch

ROS filesystem and commands

rospack – gets path about packages. **find** returns path to packages
$ rospack find roscpp
–list nodes in package- use autocomplete. $ rosrun package_name <tab><tab>

roscd – change directory directly to package or stack (don't need path)
$ roscd roscpp or $ roscd roscpp/cmake
*roscd and other ros tools will only find ros packages within directories on the ros_package_path
$ echo $ROS_PACKAGE_PATH

rosls – list information about package by name instead of by path
$ rosls roscpp_tutorials
>> cmake launch package.xml srv

rosnode
list – see what is running

$ rosnode list

-cleanup-- refreshes rosnode list (after something has been killed)

$ rosnode cleanup

info – gives publications, subscriptions, services, etc of a node

$ rosnode info /[node] ex. $ rosnode info /rosout

ping – check connection

$ rosnode ping [node_name]

rosrun – runs node

$ rosrun turtlesim turtlesim_node (optional: __name:=loggerhead)

rqt_graph – makes bubble chart graph of what is happening in the system.

$ rosrun rqt_graph rqt_graph

rqt_plot – plot the data being published on a topic in real time.

$ rosrun rqt_plot rqt_plot

rosmsg – get info about messages

$ rosmsg list #see all messages

$ rosmsg package <package-name> # see all msgs in a package

$ rosmsg packages # list the packages with msgs

rostopic – get info about topics.

Example topics: /turtle1/cmd_vel, /turtle2/pose, /rosout. Also use autocomplete

$ rostopic -h #explains the rostopic commands

$ rostopic echo [topic] #print messages to the screen

$ rostopic list #list of topics. End with -v to get verbose published and subscriptions

$ rostopic type [topic] # gives message type sent on a topic

-then to see details of the msg type, do

$ rostopic type [topic] | rosmsg show # $ rosmsg show geometry_msgs/Twist

Send ROS message manually

$ rostopic pub [topic] [msg_type] [args]

$ rostopic pub -1 /turtle1/cmd_vel geometry_msgs/Twist – '[2.0, 0, 0]' '[0, 0, 1.8]'

#the -1 means it only sends one message. Use -r to repeat ex. [-r 1] means repeat at 1hz

$ rostopic hz [topic] #show frequency a topic is being published to

rosservice – attach to client/service framework. Can use *list, call, type, find, uri*

 # turtle example services: /clear, /kill, /reset, /spawn

$ rosservice type [service] #tells the type of the argument

-$ rosservice type [service] | rossrv show #to see the actual arguments

$ rosservice call [service] [args]

ex. $ rosservice call /spawn 8 6 .5 "" #parameters x, y, theta, name(optional)

ex. $ rosservice call /clear #this reset the background color and the tracks on the turtle

rosparam – lets us store and change data on ROS parameter server. Stores int, float, bool, dict, lists.

$ rosparam -h #show commands

$ rosparam [set or get] [param_name] # set parameter

$ rosparam get / #gives all contents of parameter server

$ rosparam dump [file_name] [namespace]

ex. $ rosparam dump params.yaml

– can load yaml file into a new namespace, for example “copy”

$ rosparam load params.yaml copy

$ rosparam get /copy/background_b

ROS Basics and Conventions

http://wiki.ros.org/ROS/Patterns/Communication

rospy and roscpp – client libraries, allows ROS to communicate cross-language with python/cpp nodes

Package – software organization unit. Can hold libraries, executables, scripts… Like a folder

-Package names should follow C naming conventions: lower case, start with a letter, use underscore separators, e.g. laser_viewer

- names should be specific enough to identify what the package does. Ex. a motion planner might be called waypoint_planner, but not planner.

Node – executable that uses ROS to communicate with other nodes through topics.

-can have multiple nodes in one package

- a python script. A process that performs computation. An executable in a ROS package

- have **‘type’** and **‘name’**. ‘Type’ is the name of the executable used to launch the node, or the name given a node in the executable. ‘Name’ is what goes to other ROS nodes when it starts and how it is referred to. Name or type is declared when doing rospy.init_node(‘name’,…)

-node type- keep the type name short.
Ex. package= laser_scan, node type= view, $ rosrun laser_scan view

- node name- want default name of node to be same as executable that launches node. Rename it at startup if needed, not in code

- nodes can **publish, subscribe,** provide/use a **service**…

Topic- nodes publish/subscribe to topics to receive msgs

-Should be used for continuous data stream (sensor data, robot state…)

-many to many connection

-callbacks receive data when it is available

-data can be published/subscribed at any time, independent of senders/receivers

-publisher decides when data is sent

- should follow C naming. ex. laser_scan

- name should be descriptive. Don't call topic 'state', call it 'planner_state'.

-ex. Can have topic named 'out' on A(publisher), topic 'in' on B(subscriber), and as long as the later- defined topic name is the same and they are on same ROS master they can communicate. DON'T try to make topic names match inside nodeA and nodeB!

Message – ROS data type for subscribing/publishing to a topic

- used to auto generate class names. Must name with camelCase ex laserScan.msg

Services – used for remote calls that terminate quickly. For querying state of node or quick calculations.

-not for longer running processes or anything that might be preempted

-blocking. For requesting specific data. Semantically for processing requests

RQT_graph – nodes are circles, topics are lines

Action – actions are built on top of msgs

- should be used for anything that moves robot, or runs for a longer time with feedback during execution

-can be preempted, preemption should always be implemented cleanly by action servers

-can execute toward multiple action goals on the same server (multiple clients)

- action clients request goals

- action servers execute towards goals with function calls and callbacks

- **goal** -sent to actionServer by actionClient.

- **feedback** – sent to actionClient to give incremental progress towards goal

-SimpleActionServer only has one active goal at a time (always the most recent)

- **result** – sent from actionServer to actionClient when goal is completed. Sent only once. Ex. Moving to a location result= 'finished', but for a laser scan result= scanData

TF or tf2 – in general, where you publish coordinate frames or spatial data. There are exceptions

-holds relationships between frames over time. Lets you transform points, vectors, etc at any point in time

Creating catkin workspace

-create and build catkin workspace

```
$ mkdir -p ~/catkin_ws/src
$ cd ~/catkin_ws/
$ catkin_make
```

The catkin_make command is a convenience tool for working with catkin workspaces. Running it the first time in your workspace, it will create a CMakeLists.txt link in your 'src' folder.

To make sure your workspace is properly overlayed by the setup script, make sure ROS_PACKAGE_PATH environment variable includes the directory you're in.

```
$ echo $ROS_PACKAGE_PATH
>> /home/youruser/catkin_ws/src:/opt/ros/kinetic/share
```

ex. finished catkin workspace example (this is not what it looks like immediately after creation)

```
workspace1/       #catkin workspace

    src/               # SOURCE SPACE
      CMakeLists.txt   # 'Toplevel' CMake file, provided by catkin

      package_1/
        CMakeLists.txt     #CMakeLists.txt file for package_1
        package.xml        # Package manifest for package_1
        scripts/          # only if there are python files
            file1.py
        src/            # only if there are cpp files
            file2.cpp
        msg/            #only if there are custom msgs
            customMsg1.msg
        include/        # header files for cpp
            package_1/
                  file2.h
        action/         # only if using action: a special msg file
            action1.action
        launch/         #may be empty if not using launch files
            package_1.launch
       ...
      package_n/
        CMakeLists.txt     # CMakeLists.txt file for package_n
        package.xml        # Package manifest for package_n
```

Create a package

Package will have 1. CmakeLists.txt 2. package.xml (with dependency and meta info about the file) 3. be in its own folder (No nested packages). /scripts, /src, etc are used as needed.

1. change to source space directory of workspace

```
$ cd ~/catkin_ws/src
```

2. Now use the `catkin_create_pkg` script to create a new package called 'beginner_tutorials' which depends on std_msgs, roscpp, and rospy:

```
$ catkin_create_pkg  beginner_tutorials  std_msgs rospy roscpp
```

This will create a `beginner_tutorials` folder which contains a package.xml and a CMakeLists.txt, which have been partially filled out with the information you gave `catkin_create_pkg`.

3. Now you need to build the packages in the catkin workspace:

catkin_make combines cmake and make from standard cmake workflow
build- where cmake and make are called to configure packages.
devel-- devel space, where my executables and libraries go before installing packages

```
$ cd ~/catkin_ws
```

```
$ catkin_make
```

4. To add the workspace to your ROS environment you need to source the generated setup file:

```
$ . ~/catkin_ws/devel/setup.bash
```

Package dependencies

First order dependencies- ones we provide (std_msgs, rospy, roscpp above). Also stored in package.xml

```
$ rospack depends1 beginner_tutorials
>>    roscpp
      rospy
      std_msgs
```

overall dependencies – ros will recursively find all dependencies.
ex. Will go through roscpp, rospy, and std_msgs to find everything they depend on too

Developing

Editing - $ rosed [package_name] [file_name] #opens file in nano for editing

debugging with rqt_console
-http://wiki.ros.org/ROS/Tutorials/UsingRqtconsoleRoslaunch

copy file – $ roscp [package_name] [path_of_file] [destination_path]
ex. $ roscp rospy_tutorials AddTwoInts.srv srv/AddTwoInts.srv

Creating msg and srv

http://wiki.ros.org/ROS/Tutorials/CreatingMsgAndSrv

*see 'ROS basics and conventions' for naming help

msg – text file that describes fields of ROS message. Used to generate source code for messages in different languages. Stored in msg directory of package.

```
$ rosmsg show geometry_msgs/Twist        #do this to see an example
```

-can be int, float, string, time, array, or other msg files, header

```
ex.    Header header
       string child_frame_id
       geometry_msgs/PoseWithCovariance pose
```

Create new msg file – ex. write "int64 num" to file Num.msg in folder msg

0. $ roscd [package] # $ roscd beginner_tutorials
$ mkdir msg #make a msg directory/folder (if it doesn't exist)

$ echo "int64 num" > msg/Num.msg
- [>] overwrites anything currently in the file. Creates new file if necessary.
-Use [>>] to append to the file

1. write msg file (see step 0, above)

2. Check package.xml for: (in build_depend and exec_depend)

```
<build_depend>message_generation</build_depend>
<exec_depend>message_runtime</exec_depend>
```

3. Check CMakeLists.txt for:

```
3.1. find_package(catkin REQUIRED COMPONENTS
      ...
      message_generation
      )
3.2. catkin_package(
      ...
      CATKIN_DEPENDS message_runtime ...
      )
3.3. add_message_files(
      ## adding .msg here manually lets Cmake know when it has to reconfigure
      FILES
      msg_file1.msg                #ex. Num.msg
      ...
      )
3.4. generate_messages(
        DEPENDENCIES
        std_msgs
        #plus any other packages with .msg files you use
      )
```

4. Now you're ready to generate source files from the msg definition.

srv – srv describes a service. Made of **request** and **response.** Stored in srv directory of package

```
ex.   int64 A     #request
      int64 B     #request
      ---
      int64 Sum   #response
```

```
$ rossrv show [srv_name]          #returns the format of the service
```

Create new srv file--

1. write or copy srv file (see above, "Create new msg file" for help)
2. Exact same as for msg
3. Check CMakeLists.txt for:
   3.1. Exact same as above
   3.2.
```
add_service_files(
      FILES
      srv_file1.srv                #ex. AddTwoInts.srv
      ...
      )
3.3. generate_messages(
        DEPENDENCIES
        std_msgs
        #plus any other packages with .msg files you use
      )
```

4. Now you're ready to generate source files from the srv definition

Generating Source Files

1. Remake the package

```
# In your catkin workspace
$ roscd [package]      # roscd beginner_tutorials
```

```
$ cd ../..
$ catkin_make install
$ cd -            #cd back to the last spot?
```

Writing publisher and subscriber nodes (Python)

http://wiki.ros.org/ROS/Tutorials/WritingPublisherSubscriber%28python%29

Publisher

```
1 #!/usr/bin/env python                                              #**1**
2
3 import rospy                                                       #**2**
4 from std_msgs.msg import String
5
6 def talker():
7     pub = rospy.Publisher('chatter', String, queue_size=10)        #**3**
8     rospy.init_node('talker', anonymous=True)                      #**4**
9     rate = rospy.Rate(10) # 10hz                                   #**5**

#start loop, check flag to see if we should quit
10     while not rospy.is_shutdown():                                #**6**
11         hello_str = "hello world %s" % rospy.get_time()
12         rospy.loginfo(hello_str)      #rospy.loginfo(message).
# loginfo does print to screen, writes to node's log file, writes to rosout
# (rosout can be seen with rqt_console, good for debugging)
13         pub.publish(hello_str)         # pub.publish(message)
14         rate.sleep()     #can use rospy.sleep() to work with simulated time too
15
16 if __name__ == '__main__':                    #standard Python __main__ check
17     try:
18         talker()
19     except rospy.ROSInterruptException:
# above avoids continuing to work when node is shutdown
20         pass
```

0. Make the node executable (should not have to redo after the script is edited and resaved)

    $ chmod +x file_name.py

1. add exactly this to the top of the python script. Every python node will have this.
    `#!/usr/bin/env python`
2. import rospy
    --may want to import other things
3. name publisher
    `pub = rospy.Publisher('topic_name', msg_type, queue_size)`
4. tell rospy the name of our node. Names can't have any " / " in them (must be base name)
    `rospy.init_node('choose_node_name', anonymous=True)`
    -anonymous makes sure the node has unique name by adding numbers to the end of it
5. rate = rospy.Rate(10) #loops at 10hz
6. Start loop
    --see comments in code example
7. include python __main__ check
    --calls your function in it

8. Run catkin make
   $ cd ~/catkin_ws
   $ catkin_make
9. Before using applications, re-source the catkin setup.bash (might not be necessary with the permanent catkin source).
   $source ./devel/setup.bash

Subscriber- tutorial example

```
 1 #!/usr/bin/env python
 2 import rospy
 3 from std_msgs.msg import String
 4
 5 def callback(data):
 6     rospy.loginfo(rospy.get_caller_id() + "I heard %s", data.data)
 7
 8 def listener():
 9
10     # In ROS, nodes are uniquely named. If two nodes with the same
11     # name are launched, the previous one is kicked off. The
12     # anonymous=True flag means that rospy will choose a unique
13     # name for our 'listener' node so that multiple listeners can
14     # run simultaneously.
15     rospy.init_node('listener', anonymous=True)
#the subscriber is based on a callback function (“call later”) to listen for
messages
16
17     rospy.Subscriber("chatter", String, callback)
18
19     # spin() simply keeps python from exiting until this node is stopped
20     rospy.spin()
21
22 if __name__ == '__main__':
23     listener()
```

Subscriber- Tyler Musgraves example

```
#!/usr/bin/env python
import rospy
from std_msgs.msg import Int64

class altimeter:
      #start publisher
    def pub_altitude(self):
        self.pub = rospy.Publisher('altitude_m', Int64, queue_size = 5)
        rospy.init_node('pub_altitude', anonymous=True)
        rate = rospy.Rate(10)
        return
      #callback that gets data from topic, works with it
    def callback_alt(self, msg_alt):
        alt_ft = msg_alt.data * 3
        rospy.loginfo('altitude in m: %i ---- altitude in ft: %i' %(msg_alt.data,
                      alt_ft))
        return
      #start subscriber (using callback)
    def sub_altitude(self):
        sub = rospy.Subscriber('altitude_m', Int64, self.callback_alt)
```

```
        rospy.spin()    #callbacks get called in spin. If we want to control
                        #period, use spinOnce() and then rate.sleep() or similar
        return

if __name__=='__main__':
    try:
        plane1 = altimeter()  #create object (altimeter)
        plane1.pub_altitude() #start publisher

        while not rospy.is_shutdown():
            plane1.sub_altitude()  #run subscriber (and get data from callback)
    except rospy.ROSInterruptException:
        pass
#send messages manually with rostopic pub [topic] [msg_type] [arg]
```

Writing a Simple Service and Client (Python)

http://wiki.ros.org/ROS/Tutorials/WritingServiceClient%28python%29

Service Node

1. Write script (see example in beginner_tutorials: add_two_ints_server.py)
    a. declare node
        ex. Rospy.init_node('add_two_ints_server')
    b. declare service (see example)
        S = rospy.Service('service_name', service_type, function)
        ex. S = rospy.Service('add_two_ints', AddTwoInts, handle_add_two_ints)

2. make executable
    $ chmod +x scripts/add_two_ints_server.py

Client Node

1. Write script (see example in beginner_tutorials: add_two_ints_client.py)

```
 1 #!/usr/bin/env python                                    #always need this
 3 import sys
 4 import rospy
 5 from beginner_tutorials.srv import *
 6
 7 def add_two_ints_client(x, y):
 8     rospy.wait_for_service('add_two_ints') #blocks the service until
#add_two_ints is available
 9     try:
#create a handle for the service
10         add_two_ints = rospy.ServiceProxy('add_two_ints', AddTwoInts)
#call the handle like a normal function
11         resp1 = add_two_ints(x, y)
12         return resp1.sum
#since the type of the service is AddTwoInts, it generates the AddTwoIntsRequest
(or we can pass in our own). The return is AddTwoIntsResponse object.
13     except rospy.ServiceException, e:
14         print "Service call failed: %s"%e
15
16 def usage():
17     return "%s [x y]"%sys.argv[0]
18
```

```
 19 if __name__ == "__main__":
 20     if len(sys.argv) == 3:
 21         x = int(sys.argv[1])
 22         y = int(sys.argv[2])
 23     else:
 24         print usage()
 25         sys.exit(1)
 26     print "Requesting %s+%s"%(x, y)
 27     print "%s + %s = %s"%(x, y, add_two_ints_client(x, y))
```

a. Call the service
    rospy.wait_for_service('service_name')
b. make a handle for the service
    add_two_ints = rospy.ServiceProxy('add_two_ints', AddTwoInts)
c. Then use the handle like a normal function
    resp1 = add_two_ints(x, y)
    return resp1.sum

Using a Simple Action Server (python)

- see 7.2 http://wiki.ros.org/actionlib
-for api details, see
https://docs.ros.org/api/actionlib/html/classactionlib_1_1simple__action__server_1_1SimpleActionServer.html

-Example given that we have defined DoDishes.action in the 'chores' package:

```
#! /usr/bin/env python
import roslib
roslib.load_manifest('my_pkg_name')
import rospy
import actionlib
from chores.msg import DoDishesAction

class DoDishesServer:
  def __init__(self):
#this creates a DoDishes action server named 'do_dishes'
    self.server = actionlib.SimpleActionServer('do_dishes', DoDishesAction,
self.execute, False)
    self.server.start()

  def execute(self, goal):
    # Do lots of awesome groundbreaking robot stuff here
    self.server.set_succeeded()


if __name__ == '__main__':
  rospy.init_node('do_dishes_server')
  server = DoDishesServer()
 rospy.spin()
```

Recording and playing back data (bag file)

http://wiki.ros.org/ROS/Tutorials/Recording%20and%20playing%20back%20data

-Record data from a running ROS system into a .bag file, then play back the data to produce similar behavior in a running system.
- commands that are timing-sensitive might not be replayed perfectly. It will get you close, but don't expect too much

0. rosrun everything we want
1. See all running topics
   $ rostopic list -v
2. Make temporary directory
   $ mkdir ~/bagfiles
   $ cd ~/bagfiles
3. Record topics
   $ rosbag record -a #record all topics
   $ rosbag record -O subset /turtle1/cmd_vel /turtle1/pose #record only topics in subset.bag
4. Playback topics
   $ rosbag play <bagfile.bag> #playback at normal speed
   $ rosbag play -r 2 <bagfile.bag> #playback at double speed

Simulators and etc (next steps)

http://wiki.ros.org/ROS/Tutorials/WhereNext

TODO – add a section on actions

Managing your environment

-during installation you have to source one of several setup.*sh files
-check environment variables like ROS_ROOT and ROS_PACKAGE_PATH with
   $ printenv | grep ROS

CmakeLists.txt example

For a package "beginner_tutorials" with:
   - 1 service, 1 msg
   -multiple python files in /scripts
   -no c++ files

```
cmake_minimum_required(VERSION 2.8.3)
project(beginner_tutorials)   #the package name

find_package(catkin REQUIRED COMPONENTS
      roscpp
      rospy
      std_msgs
      message_generation
)

add_message_files(FILES
```

```
      Num.msg
)
add_service_files(FILES
      AddTwoInts.srv
)
generate_messages(DEPENDENCIES
      std_msgs
)
catkin_package(
CATKIN_DEPENDS roscpp rospy std_msgs message_runtime
)
include_directories(
${catkin_INCLUDE_DIRS}
)
```

package.xml example

- for the same package as above

```
<package format="2">
<name>beginner_tutorials</name>
<version>0.0.1</version>
<description>Tyler's tutorial description</description>
<maintainer email="tm@todo.todo">tm</maintainer>
<license>BSD</license>

<buildtool_depend>catkin</buildtool_depend>

<build_depend>message_generation</build_depend>
<exec_depend>message_runtime</exec_depend>
<build_depend>roscpp</build_depend>
<build_depend>rospy</build_depend>
<build_depend>std_msgs</build_depend>
<build_export_depend>roscpp</build_export_depend>
<build_export_depend>rospy</build_export_depend>
<build_export_depend>std_msgs</build_export_depend>
<exec_depend>roscpp</exec_depend>
<exec_depend>rospy</exec_depend>
<exec_depend>std_msgs</exec_depend>

<export>
</export>
</package>
```

Linux Notes

apt-cache search ros-kinetic | **grep** python

-grep searches the output for the words "python" and highlights it

pwd – print working directory

cat – show file $ cat package.xml

Transfer file from one user to another

```
cp  file_name  /tmp/
chmod  a+r  /tmp/file_name
```

```
sudo -u user_two cp /tmp/file ~user_two
rm /tmp/file_name
```