

Übungsblatt 1

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Aufgabe 1 ():

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juauer@juauer-vm: /opt/ros/jade/share/roscpp$
setting /run_id to f266aaa-7bce-11e5-b307-000c29da8225
process[rosout-1]: started with pid [32159]
started core service [/rosout]
^C[rosout-1] killing on exit
[master] killing on exit
shutting down processing monitor...
... shutting down processing monitor complete
done
unhandled exception in thread started by
sys.excepthook is missing
lost sys.stderr
juauer@juauer-vm: /opt/ros/jade/share/roscpp$ man roscore
Kein Handbucheintrag für roscore vorhanden
Siehe auch »man 7 undocumented« für Hilfe, wenn Handbuchseiten nicht verfügbar s
juauer@juauer-vm: /opt/ros/jade/share/roscpp$ man roscore
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juauer@juauer-vm: /opt/ros/jade/share/roscpp$ roscore
... logging to /home/juauer/.ros/log/4322545a-7bcf-11e5-b87a-000c29da8225/roslau
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://juauer-vm:35335/
ros_comm version 1.11.13

SUMMARY
=====
PARAMETERS
 * /roslstroz: jade
 * /rosversion: 1.11.13

NODES
auto-starting new master
process[master]: started with pid [32234]
ROS_MASTER_URI=http://juauer-vm:11311/

setting /run_id to 4322545a-7bcf-11e5-b87a-000c29da8225
process[rosout-1]: started with pid [32247]
started core service [/rosout]
^C[rosout-1] killing on exit
[master] killing on exit
shutting down processing monitor...
... shutting down processing monitor complete
done
juauer@juauer-vm: /opt/ros/jade/share/roscpp$

```

```

juauer@juauer-vm: /opt/ros/jade/share/roscpp$
juauer@juauer-vm: /opt/ros/jade/share/roscpp$ roscore list
/roscout
juauer@juauer-vm: /opt/ros/jade/share/roscpp$ roscore info /roscout
-----
Node [/roscout]
Publications:
 * /roscout_agg [roscgraph_msgs/Log]

Subscriptions:
 * /roscout [unknown type]

Services:
 * /roscout/set_logger_level
 * /roscout/get_loggers

contacting node http://juauer-vm:38158/ ...
Pid: 32247
juauer@juauer-vm: /opt/ros/jade/share/roscpp$

```

Abbildung 1: Aufsetzen: check

Aufgabe 2 ():

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juauer@juauer-vm: /opt/ros/jade/share/roscpp$
juauer@juauer-vm: /opt/ros/jade/share/roscpp$ roscore list
/roscout
juauer@juauer-vm: /opt/ros/jade/share/roscpp$ roscore info /roscout
-----
Node [/roscout]
Publications:
 * /roscout_agg [roscgraph_msgs/Log]

Subscriptions:
 * /roscout [unknown type]

Services:
 * /roscout/set_logger_level
 * /roscout/get_loggers

contacting node http://juauer-vm:38158/ ...
Pid: 32247

juauer@juauer-vm: /opt/ros/jade/share/roscpp$ roscore turtlesim turtlesim_node
[ERROR] [1445857510.268938518]: [registerPublisher] Failed to contact master at
[ INFO] [1445857517.340582735]: Connected to master at [localhost:11311]
[ INFO] [1445857517.690180700]: Starting turtlesim with node name /turtlesim
[ INFO] [1445857517.699775330]: Spawning turtle [turtle1] at x=[5.544445], y=[5.544445], theta=[0.000000]

juauer@juauer-vm: /opt/ros/jade/share/roscpp$ roscore turtlesim turtle_teleop_key
Reading from keyboard
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Use arrow keys to move the turtle.

```

```

juauer@juauer-vm: /opt/ros/jade/share/roscpp$
juauer@juauer-vm: /opt/ros/jade/share/roscpp$ roscore turtlesim turtlesim_node
turtlesim_node turtlesim_teleop_key
juauer@juauer-vm: /opt/ros/jade/share/roscpp$ roscore turtlesim turtlesim_node
[ INFO] [1445857805.322590565]: Starting turtlesim with node name /turtlesim
[ INFO] [1445857805.334549377]: Spawning turtle [turtle1] at x=[5.544445], y=[5.544445], theta=[0.000000]

```

Abbildung 2: Nodes verstehen: check