

Introduction to ROS

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All slides are available here:

<https://github.com/project-omicron/robocar/>

History of ROS

ROS motivation



No single solution how to program robots

Eric Berger and Keenan WYROBEK, PhD students at Stanford, build PR1 (Personal Robot One) and began to work on software from it, borrowing the best practices from other early open source robotic software frameworks

Early funding of US\$50,000 was provided by Joanna Hoffman and Alain Rossmann, which supported the development of the PR1

Outcome



ROS provides rich selection of packages

ROS has a huge set of tools to design robots

A new version of ROS every year

ROSCons occurs every year since 2012

Robotnaut 2: first ROS based robot in space

ROS2 was released

Structure of ROS

What is a workspace in ROS

Workspace is the folder inside which you are going to be actively developing. Keeping things in a folder with connected development helps keep separation of development models

Catkin is a low-level build system macros and infrastructure for ROS

Catkin workspace is a folder where you modify, build, and install catkin packages

For more information, check: [ROS catkin documentation](#)

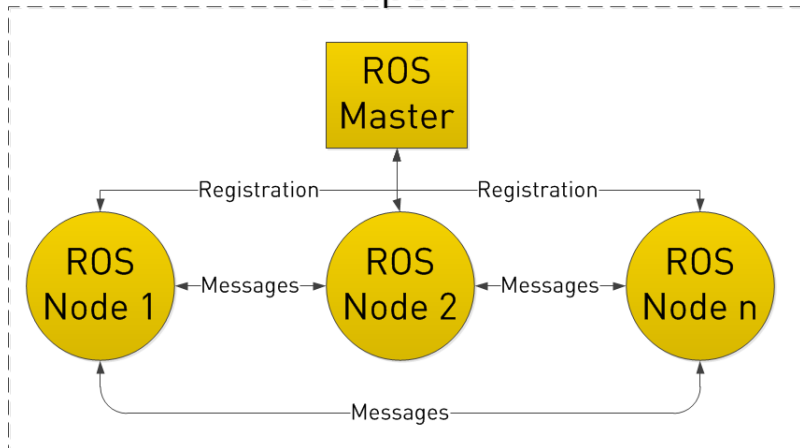
Introduction to catkin_init_workspace and catkin_make

catkin_init_workspace initializes a catkin workspace by creating a top level CMakeLists.txt

catkin_make is a convenience tool for building code in a catkin workspace. catkin_make follows the standard layout of a catkin workspace

Robot architecture in ROS, example

Computer 1



ROS Master

The ROS Master provides naming and registration services to the rest of the nodes in the ROS system.

- Tracks publishers and subscribers nodes
- Tracks topics
- Tracks services
- Provide parameter server

Shared, multi-variate dictionary, accessible via network APIs.

Nodes use this server to store and retrieve parameters at runtime.

Publisher vs. Subscriber

Publisher: Node that puts information to the topic

Subscriber: Node that checks if the information arrives to the topic.
Once the information arrived, it can react correspondingly

In ROS, every node can be a publisher, subscriber or both

For more info, check [here](#)

What is the topic in ROS

Topic is a named buse over which nodes exchange messages

Each topic is strongly typed by the ROS message type

ROS currently supports TCP/IP-based and UDP-based message transport

- 1 TCPROS is the default transport used in ROS
- 2 UDP-based transport is currently only supported in roscpp

Introduction to the command rostopic

rostopic is a command-line tool for interacting with ROS topics

Once you run the robot, you can see all available topics

rostopic list

Current value in the topic

rostopic echo /topic_name

Information about the frequency of the topic

rostopic hz /topic_name

More information: [ROS Topic](#)

What is the service in ROS

Request/reply is done via a Service, which is defined by a pair of messages: one for the request and one for the reply.

Services are defined using srv files.

Generally saying: service is the RPC in ROS.

Introduction to the command rosservice

rosservice contains the rosservice command-line tool for listing and querying ROS Services

List all the services that are currently available

rosservice list

Print information about specified service *rosservice info /rosout*

Call a service from the command line

rosservice call /service_name service-args

For more information: [ROS Service](#)

MUX

mux is a ROS node that subscribes to a set of incoming topics and republishes incoming data from one of them to another topic

Example:

We use mux to switch from AI controller to human controller.

More information and examples: [ROS mux](#)

roscore and rosruntime

roscore is a collection of nodes and programs that are pre-requisites of a ROS-based system. You **must** have a roscore running in order for ROS nodes to communicate.

roslaunch allows you to run an executable in an arbitrary package from anywhere without having to give its full path or `cd/roscd` there first.

Example:

```
roscore
```

```
roslaunch package node _parameter:=value
```

For more information, see [ROS roslaunch](#), [ROS roscore](#)

roslaunch

roslaunch is a tool for easily launching multiple ROS nodes locally and remotely via SSH, as well as setting parameters on the Parameter Server.

roslaunch takes in one or more XML configuration files (with the .launch extension) that specify the parameters to set and nodes to launch, as well as the machines that they should be run on.

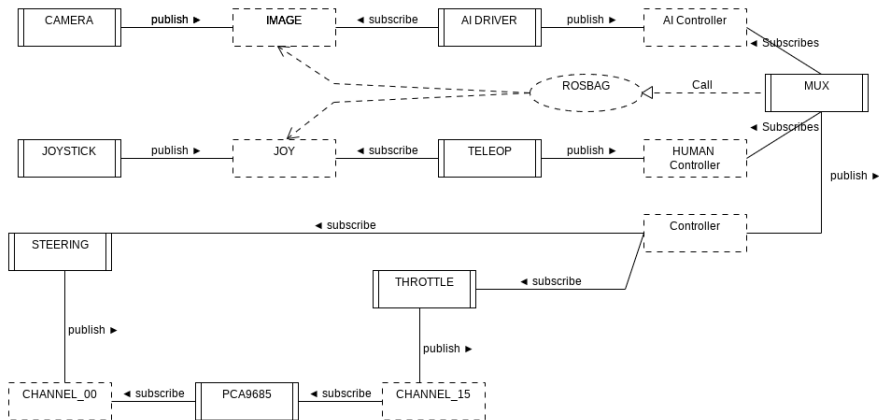
Example:

roslaunch package_name file.launch

For more information, see [ROS roslaunch](#)

Project OMICRON

High level description of nodes



Thank you!

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Whant to know more? Useful links

The Origin Story of ROS, the Linux of Robotics

ROS History, ROS.org

ROS, wiki page

ROS Industrial ROS Tutorial for publisher and subscriber