ROS2 RIEGL VZ Package API

1. Coordinate Systems

SOCS (Scanner's Own Coordinate System):

Angle data and range data are the base for calculation of the data in the Scanner's Own Coordinate System (SOCS).

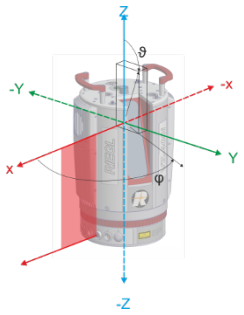

Figure 1: SOCS (Scanner's Own Coordinate System)

PRCS (Project Coordinate System):

A number of scan positions and the data acquired therein make up a scan project. The center of the project's coordinate system (PRCS) coincides horizontally with the center of the first scan position. The axes of PRCS are strictly pointing to east (x-axis, red), north (y-axis, green) and up (z-axis, blue), respectively.

The SOP transforms SOCS into PRCS.

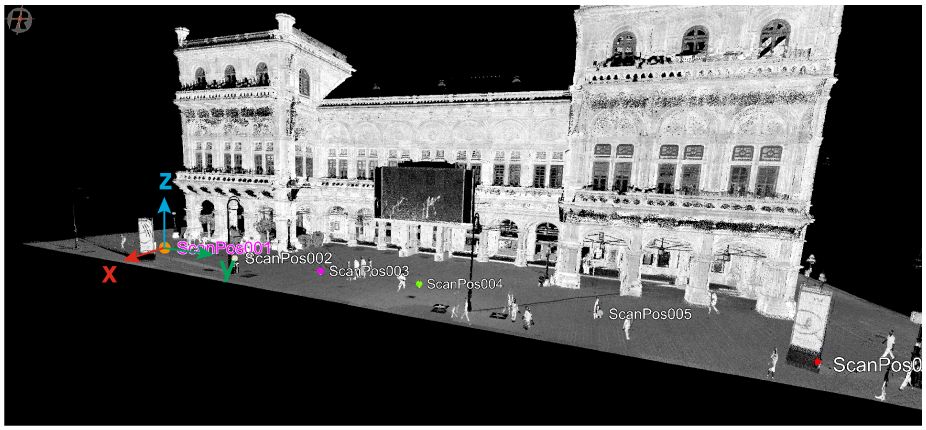

Figure 2: PRCS (Project Coordinate System)

GLCS (Global Coordinate System):

A global coordinate system like WGS84.

The POP transforms GLCS into PRCS

VOCS (Voxel Coordinate System):

Automatic registration does not estimate the SOP with every new scan position, but the SOPV pose, which does not transform to PRCS, but to another cartesian coordinate system, the so called VOCS (Voxel Coordinate System). A once determined SOPV pose stays unchanged. What changes is the VOP. The VOP pose is determined via compensation of a fixed block of registered scan positions against all further measurements. Further measurements are the scanners inclination, northing from internal magnitude sensor, which is fraught with great uncertainty, and GNSS position if available.

After first scan: VOP = eye(4)
After each consecutive scan: VOP <> eye(4)

If the user is only interested in relative registration of scan positions to each other, the VOP and the POP can be ignored.

2. RIEGL Interfaces

2.1 Messages

riegl_vz_interfaces/ScanPose:

```
uint32 seq   # Scan position number within a project
geometry_msgs/PoseStamped pose
```

'seq' is the scan position number.
See PoseStamped definition: geometry_msgs/PoseStamped

2.2 Services

riegl_vz_interfaces/GetScanPoses:

```
---
string project                # Scan project name
ScanPose[] scanposes
geometry_msgs/PoseStamped vop # position and orientation of VOCS in PRCS
geometry_msgs/PoseStamped pop # position and orientation of PRCS in GLCS
bool success                  # indicate successful run of service
string message                # informational, e.g. for error messages
```

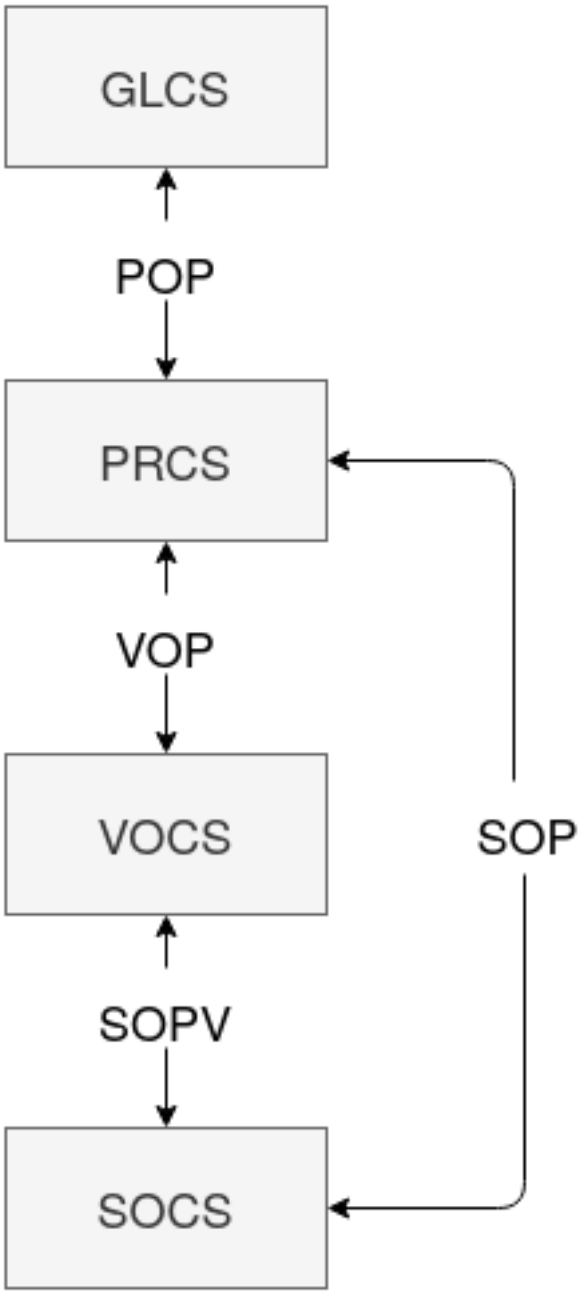

Figure 3: RIEGL Coordinate Systems

The ‘frame_id’ in the scanposes[n].header is ‘riegl_vz_vocs’.
The ‘frame_id’ in the vop.header is ‘riegl_vz_prcs’.
The ‘frame_id’ in the pop.header is ‘riegl_vz_glcs’, which is e.g. EPSG::4978

riegl_vz_interfaces/SetPosition:

```
geometry_msgs/PointStamped position
---
bool success   # indicate successful run of service
string message # informational, e.g. for error messages
```

See PointStamped definition: geometry_msgs/PoseStamped The ‘frame_id’ in the position.header is ‘riegl_vz_glcs’, which is e.g. EPSG::4978

3. Nodes

3.1 riegl_vz

3.1.1 Parameters

~**hostname** (string, default: “”) :

The scanners hostname or IP address.

~**working_dir** (string, default: “/tmp/ros_riegl_vz”) :

The root working directory for runtime execution.

~**ssh_user** (string, default: “user”) :

The linux user name for SSH login on the scanner.

~**ssh_password** (string, default: “user”) :

The linux user password for SSH login on the scanner.

~**project_name** (string, default: “”) :

The name of the project to be loaded or created.

~**storage_media** (integer, default: 0) :

The active storage media for scan data recording (0: INTERNAL SSD, 1: USB, 2: SD CARD).

~**scan_pattern** (double[], default: {30.0,130.0,0.04,0.0,360.0,0.04})

Specifies the field of view (FOV) for scanning and the scan increments.
[0]: Line Start Angle
[1]: Line Stop Angle
[2]: Line Angle Increment
[3]: Frame Start Angle

[4]: Frame Stop Angle
[5]: Frame Angle Increment

~**scan_pattern_name** (string, default: “”)

Name of a factory or user defined scan pattern, which is for example ‘Overview’ or ‘Panorama_40’.
If pattern is available and not empty, this overwrites the configuration values from ‘~scan_pattern’.

~**meas_program** (integer, default: 3)

This is the laser scanner measurement program, which specifies the laser scanner frequency.

~**scan_publish** (bool, default: “True”) :

Enable publishing of point cloud data on topic ‘pointcloud’ after scan acquisition has finished.

~**scan_publish_filter** (string, default: “”) :

Filter string for published point cloud data, e.g. “(riegl.xyz[2] $>$ 5) && (riegl.reflectance $>$ 35)”

~**scan_publish_lod** (integer, default: 0) :

Level of detail (LOD) for published point cloud. This is to reduce the number of measurements.
lod=0 : no reduction
lod=1 : reduce measurements by factor 2 (2^1)
lod=2 : reduce point cloud by factor 4 (2^2)
lod=3 : reduce point cloud by factor 8 (2^3)
...

~**scan_register** (bool, default: “True”) :

Enable automatic scan position registration in current project after scan data acquisition has finished.

~**pose_publish** (bool, default: “True”) :

Enable publishing of scan registration result on topic ‘pose’ after scan registration has finished.

~**reflector_search** (bool, default: “False”) :

Enable automatic reflector search with every scan data acquisition.

~**reflector_search_models** (string, default: “”) :

Name of reflector search model. Can be specified multiple times, separated by comma (e.g. “RIEGL flat reflector 50 mm, RIEGL flat reflector 100 mm”)

~**reflector_search_limits** (double[], default: {0.0,10000.0}) :

Minimum and maximum range in meter between scan-position and reflector.

~control_points_csv_file (string, default: “”) :

Path to CSV with control points in GLCS (Global Coordinate System).

~control_points_coord_system (string, default: “”) :

The coordinate system for control points (e.g. EPSG::4978).

~image_capture (integer, default: 0) :

Configures capturing of images with external camera mounted on top of RIEGL Vz laser scanner. (0=disabled, 1=enabled, 2=automatic)

~image_capture_mode (integer, default: 1) :

The image capture mode (1=during-scan, 2=after-scan).

~image_capture_overlap (integer, default: 25) :

The image overlap factor in percent.

3.1.2 Published Topics

pointcloud (sensor_msgs/PointCloud2) :

Point cloud with scan data from the laser scanner. Included are xyz cartesian coordinates in SOCS and reflectance in dB. Data will be published only if parameter ‘~scan_publish’ is enabled.

pose (geometry_msgs/PoseStamped):

Topic provides SOPV (Scan Position and Orientation in VOCS) of the currently registered scan position.

gnss (sensor_msgs/NavSatFix.msg) :

Actual GNSS fix with position in WGS 84 coordinates, published once per second.

diagnostics (diagnostic_msgs/DiagnosticArray.msg):

Riegl VZ status information, published once per second:

```
scanner:
  opstate       : operating state ("unavailable", "waiting", "scanning", "processing")
  active_task   : active task description
  progress      : scan progress in percent
  scan_position : number of current scan position
  laser         : laser state 'on' or 'off'
errors:
  warn_num      : number or pending system warnings
  err_num       : number of pending system
```

```
memory:
  mem_free_gb   : free storage media memory space in GByte
  mem_usage     : storage media memory usage in percent of total space
gnss:
  gnss_fix      : GNSS fix
  gnss_num_sat  : number of available satellites
camera:
  cam_detect    : external camera detected
```

3.1.3 Services

set_project (std_srvs/Trigger) :

Load an existing project on the scanner with name from parameter '~project_name'. If the project name is empty or the project can not be loaded, a new project will be created automatically.

Response:
success = True -> message: Project Name

set_position (riegl_vz_interfaces/SetPosition) :

Set position of the scanner origin in a global coordinate system (GLCS) supported by RIEGL GeoSys Manager. The position must be set before the scan. This allows transformation of scans into a global coordinate system and furthermore the position is an initial guess for scan registration.

scan (std_srvs/Trigger) :

Start a background task for laser scan data acquisition.

The execution state will be published in 'opstate' field of 'diagnostics' topic. The node is locked until all background tasks have finished and the operating state is 'waiting' again.

If parameter '~scan_publish' is enabled, acquired data will be published on 'pointcloud' topic soon after scanning has finished.

The parameter '~scan_register' enables automatic scan position registration after scanning. The registration result is published on topic 'pose' and with TF2 broadcast messages (see 3.1.4).

The parameter '~reflector_search' activates automatic search and scan of reflector targets.

The parameter '~image_capture' enables automatic capturing of images with an external camera mounted on top of the laser scanner device.

Response:
success = True -> message: "success"

success = False -> message: “device not available” | “device is busy” | “command execution error”

get_scan_poses (riegl_vz_interfaces/GetScanPoses) :

Request all positions and orientations of previously registered scans of the actual project.

Response:
success = True -> message: “success”, project: Project Name, scanposes: All Scan Poses, vop: VOP Pose, pop: POP Pose
success = False -> message: “device not available” | “command execution error”

stop (std_srvs/Trigger) :

Stop laser scan data acquisition and registration background tasks.

Response:
success = True -> message: “success”
success = False -> message: “device not available” | “command execution error”

shutdown (std_srvs/Trigger) :

Stop data acquisition and power down the laser scanner device.

Response:
success = True -> message: “success”
success = False -> message: “command execution error”

3.1.4 TF2 Transformation

The node will broadcast TF2 transformation messages if an existing project is loaded and after each scan position registration:

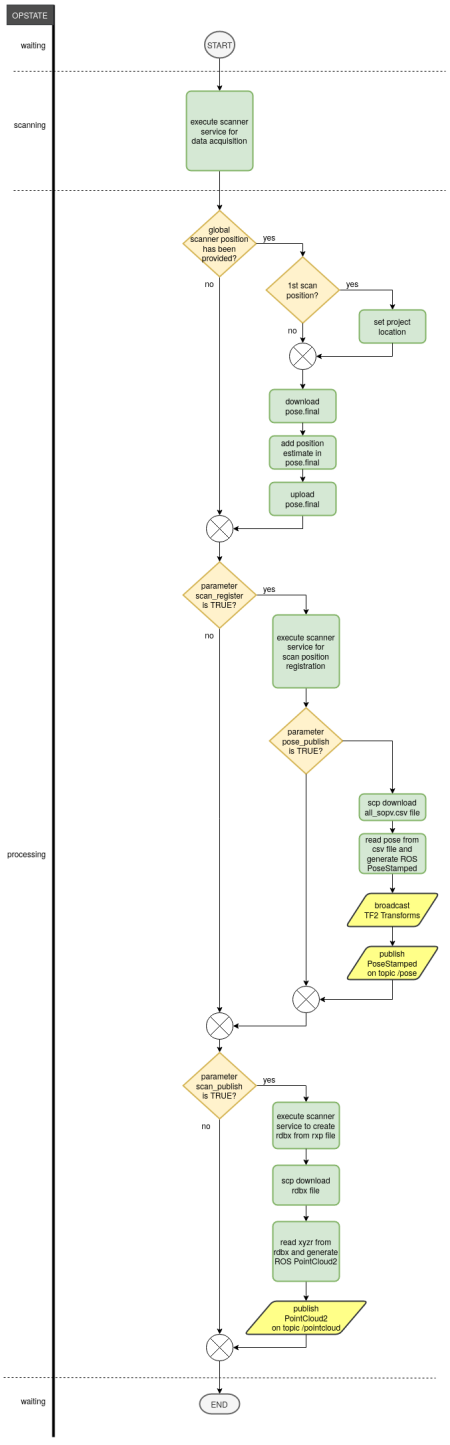

Figure 4: ROS Scan Service

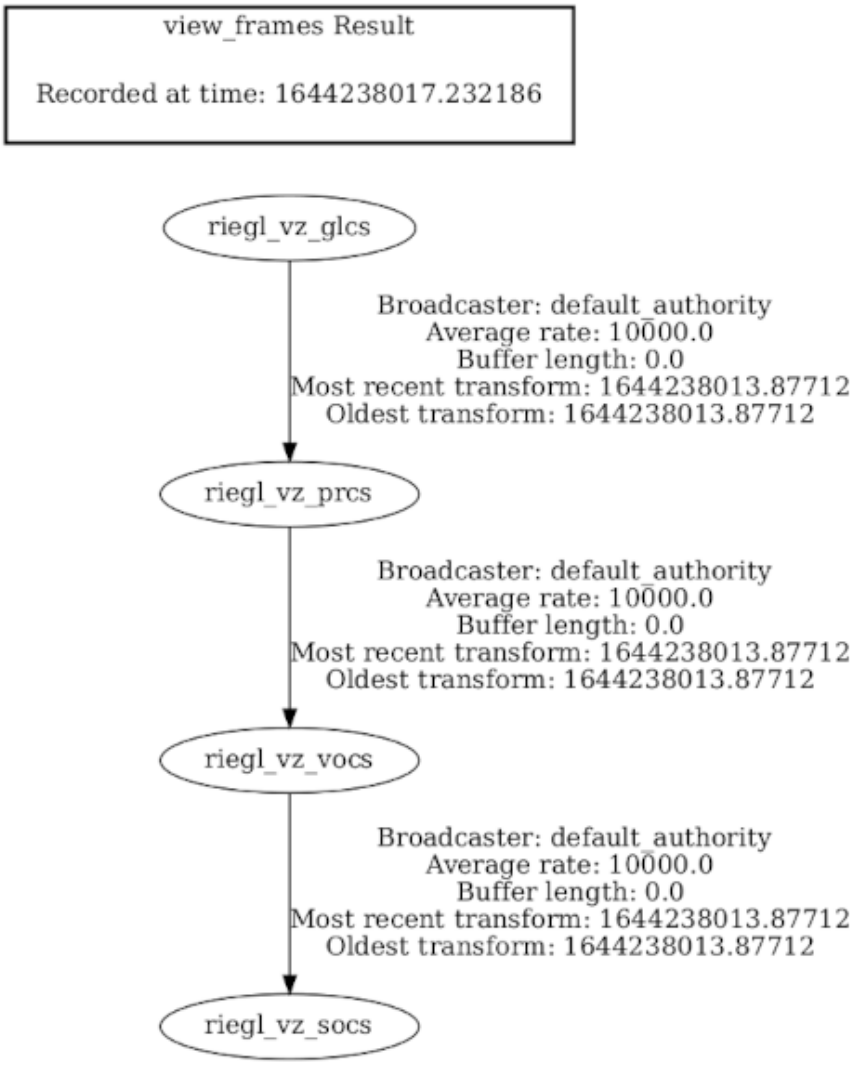

Figure 5: TF2 Transformation