

# Test of rotation node

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# Test of rotation node (1/5)

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1. You should be connected to a platform;
  2. In a first terminal, we will run the rotation node;
  3. In a second terminal, we will publish a `/rotation_to_do`.
- We will watch the mobile robot performing the `/rotation_to_do` and the output of the `rotation_action` node.

# Test of rotation node (2/5)

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- Display of the first terminal
- The rotation\_action node is waiting for a /rotation\_to\_do to perform

```
olivier@pc-robair:~/catkin_ws$ rosrun rotation_action rotation_action_node  
[ INFO] [1490262743.490274477]: (rotation_node) waiting for a rotation to perform
```

# Test of rotation node (3/5)

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- Display of the second terminal
- We publish a /rotation\_to\_do of 1.57 radians

```
olivier@pc-robair:~/catkin_ws$ rostopic pub -1 /rotation_to_do std_msgs/Float32 -- 1.57
```

# Test of rotation node (4/5)

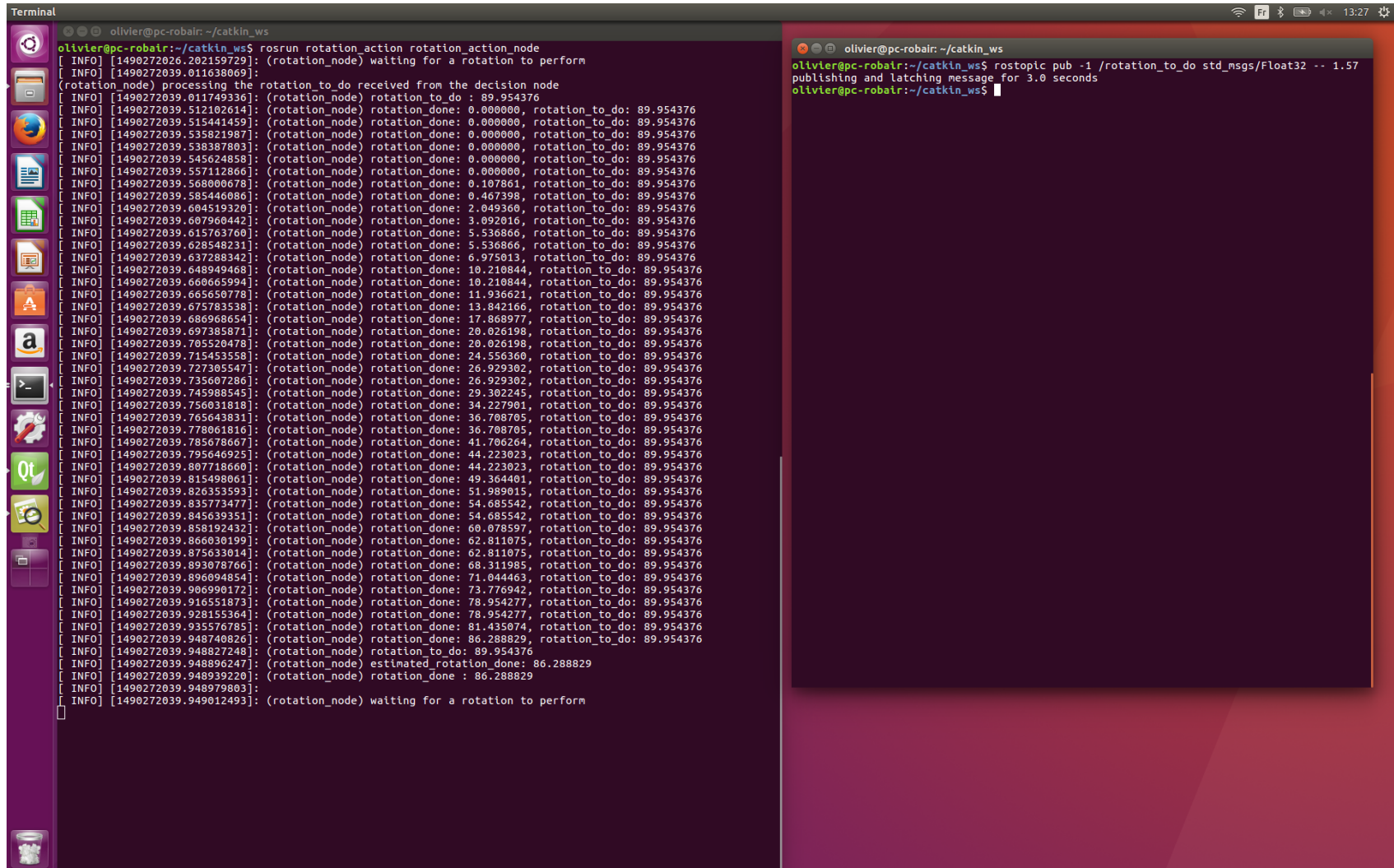
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- Display of the second terminal
- We publish `/rotation_to_do` of 1.57 radians

```
olivier@pc-robair:~/catkin_ws$ rostopic pub -1 /rotation_to_do std_msgs/Float32 - 1.57
```

# Test of rotation node (5/5)

- Display of both terminals after execution of /rotation\_to\_do



The image displays two terminal windows side-by-side, showing the execution of a ROS2 rotation node. The left terminal window shows the output of the `rosrun rotation_action rotation_action_node` command, which prints a series of log messages indicating the node is waiting for a rotation to perform, then processing the `/rotation_to_do` received from the decision node, and finally publishing the rotation done message. The right terminal window shows the output of the `rostopic pub -1 /rotation_to_do std_msgs/Float32 -- 1.57` command, which publishes and latches the message for 3.0 seconds.

```
olivier@pc-robair: ~/catkin_ws
olivier@pc-robair:~/catkin_ws$ rosrun rotation_action rotation_action_node
[ INFO] [1490272026.202159729]: (rotation_node) waiting for a Rotation to perform
[ INFO] [1490272039.011638069]: (rotation_node) processing the rotation_to_do received from the decision node
[ INFO] [1490272039.011749336]: (rotation_node) rotation_to_do : 89.954376
[ INFO] [1490272039.512102614]: (rotation_node) rotation_done: 0.000000, rotation_to_do: 89.954376
[ INFO] [1490272039.515441459]: (rotation_node) rotation_done: 0.000000, rotation_to_do: 89.954376
[ INFO] [1490272039.535821987]: (rotation_node) rotation_done: 0.000000, rotation_to_do: 89.954376
[ INFO] [1490272039.538387803]: (rotation_node) rotation_done: 0.000000, rotation_to_do: 89.954376
[ INFO] [1490272039.545624858]: (rotation_node) rotation_done: 0.000000, rotation_to_do: 89.954376
[ INFO] [1490272039.557112866]: (rotation_node) rotation_done: 0.000000, rotation_to_do: 89.954376
[ INFO] [1490272039.568000678]: (rotation_node) rotation_done: 0.107861, rotation_to_do: 89.954376
[ INFO] [1490272039.585446086]: (rotation_node) rotation_done: 0.467398, rotation_to_do: 89.954376
[ INFO] [1490272039.604519320]: (rotation_node) rotation_done: 2.049360, rotation_to_do: 89.954376
[ INFO] [1490272039.607960442]: (rotation_node) rotation_done: 3.092016, rotation_to_do: 89.954376
[ INFO] [1490272039.615763760]: (rotation_node) rotation_done: 5.536866, rotation_to_do: 89.954376
[ INFO] [1490272039.628548231]: (rotation_node) rotation_done: 5.536866, rotation_to_do: 89.954376
[ INFO] [1490272039.637288342]: (rotation_node) rotation_done: 6.975013, rotation_to_do: 89.954376
[ INFO] [1490272039.648949468]: (rotation_node) rotation_done: 10.210844, rotation_to_do: 89.954376
[ INFO] [1490272039.660665994]: (rotation_node) rotation_done: 10.210844, rotation_to_do: 89.954376
[ INFO] [1490272039.665650778]: (rotation_node) rotation_done: 11.936621, rotation_to_do: 89.954376
[ INFO] [1490272039.675783538]: (rotation_node) rotation_done: 13.842166, rotation_to_do: 89.954376
[ INFO] [1490272039.686968654]: (rotation_node) rotation_done: 17.868977, rotation_to_do: 89.954376
[ INFO] [1490272039.697385871]: (rotation_node) rotation_done: 20.026198, rotation_to_do: 89.954376
[ INFO] [1490272039.705520478]: (rotation_node) rotation_done: 20.026198, rotation_to_do: 89.954376
[ INFO] [1490272039.715453558]: (rotation_node) rotation_done: 24.556360, rotation_to_do: 89.954376
[ INFO] [1490272039.727305547]: (rotation_node) rotation_done: 26.929302, rotation_to_do: 89.954376
[ INFO] [1490272039.735607286]: (rotation_node) rotation_done: 26.929302, rotation_to_do: 89.954376
[ INFO] [1490272039.745988545]: (rotation_node) rotation_done: 29.302245, rotation_to_do: 89.954376
[ INFO] [1490272039.756031818]: (rotation_node) rotation_done: 34.227901, rotation_to_do: 89.954376
[ INFO] [1490272039.765643831]: (rotation_node) rotation_done: 36.708705, rotation_to_do: 89.954376
[ INFO] [1490272039.778061816]: (rotation_node) rotation_done: 36.708705, rotation_to_do: 89.954376
[ INFO] [1490272039.785678667]: (rotation_node) rotation_done: 41.706264, rotation_to_do: 89.954376
[ INFO] [1490272039.795646925]: (rotation_node) rotation_done: 44.223023, rotation_to_do: 89.954376
[ INFO] [1490272039.807718660]: (rotation_node) rotation_done: 44.223023, rotation_to_do: 89.954376
[ INFO] [1490272039.815498061]: (rotation_node) rotation_done: 49.364401, rotation_to_do: 89.954376
[ INFO] [1490272039.826353593]: (rotation_node) rotation_done: 51.989015, rotation_to_do: 89.954376
[ INFO] [1490272039.835773477]: (rotation_node) rotation_done: 54.685542, rotation_to_do: 89.954376
[ INFO] [1490272039.845639351]: (rotation_node) rotation_done: 54.685542, rotation_to_do: 89.954376
[ INFO] [1490272039.858192432]: (rotation_node) rotation_done: 60.078597, rotation_to_do: 89.954376
[ INFO] [1490272039.866030199]: (rotation_node) rotation_done: 62.811075, rotation_to_do: 89.954376
[ INFO] [1490272039.875633014]: (rotation_node) rotation_done: 62.811075, rotation_to_do: 89.954376
[ INFO] [1490272039.893078766]: (rotation_node) rotation_done: 68.311985, rotation_to_do: 89.954376
[ INFO] [1490272039.896094854]: (rotation_node) rotation_done: 71.044403, rotation_to_do: 89.954376
[ INFO] [1490272039.906990172]: (rotation_node) rotation_done: 73.776942, rotation_to_do: 89.954376
[ INFO] [1490272039.916551873]: (rotation_node) rotation_done: 78.954277, rotation_to_do: 89.954376
[ INFO] [1490272039.928155364]: (rotation_node) rotation_done: 78.954277, rotation_to_do: 89.954376
[ INFO] [1490272039.935576785]: (rotation_node) rotation_done: 81.435074, rotation_to_do: 89.954376
[ INFO] [1490272039.948740826]: (rotation_node) rotation_done: 86.288829, rotation_to_do: 89.954376
[ INFO] [1490272039.948827248]: (rotation_node) rotation_to_do : 89.954376
[ INFO] [1490272039.948896247]: (rotation_node) estimated_rotation_done: 86.288829
[ INFO] [1490272039.948939220]: (rotation_node) rotation_done : 86.288829
[ INFO] [1490272039.948979803]: (rotation_node) rotation_to_do : 86.288829
[ INFO] [1490272039.949012493]: (rotation_node) waiting for a rotation to perform
```

```
olivier@pc-robair:~/catkin_ws
olivier@pc-robair:~/catkin_ws$ rostopic pub -1 /rotation_to_do std_msgs/Float32 -- 1.57
publishing and latching message for 3.0 seconds
olivier@pc-robair:~/catkin_ws$
```