



UiS Marine and Offshore MSc



An international university campus across 1300 acres of land



ROS 2-Gazebo - Marine Simulator v1.2



Professor Yihan Xing
Study program leader, MSc Marine and Offshore

Updates from MARSIM v1.1

- Corrected DVL sensor mounting
- marsim_gazebo
 - New launch files
 - launch/complete_simlaunch_bluerov2.launch
- marsim_control
 - New scripts:
 - scripts/bluerov2_pid_pose_xyyaw_reqcontrol.py
 - scripts/bluerov2_pid_pose_z_reqcontrol.py
 - scripts/bluerov2_stop_thrusters.py
 - Updated scripts:
 - scripts/bluerov2_pid_pose_z_control.py

Corrected DVL sensor mounting

- Vel_x and Vel_y were inverted
 - Fixed by changing `<pose degrees="true">0.0 0 -0.12 0 0 180</pose>` to `<pose degrees="true">0.0 0 -0.12 0 0 0</pose>`
- Pos_x and Pos_y from the EKF was inverted
 - Fixed by deleting `<reference_frame>0 0 0 0 0 -1.570796</reference_frame>`

Updated scripts/bluerov2_pid_pose_z_control.py

```
133         # Create thruster commands
134         # Assuming thrusters 5 and 6 (indices 4 and 5) are responsible for vertical motion
135         # Positive thrust for T5 and T6 pushes the ROV down
136         thruster_commands = [0.0] * 6
137         thruster_commands[4] = -output
138         thruster_commands[5] = -output
```



```
150         # Create thruster commands
151         # Assuming thrusters 5 and 6 (indices 4 and 5) are responsible for vertical motion
152         # Positive thrust for T5 and T6 pushes the ROV down
153         thruster_commands = [None] * 6
154         thruster_commands[4] = -output
155         thruster_commands[5] = -output
156
```

- The script will now not send any commands now to T1, T2, T3 and T4.
- This allows T1 to T4 to receive commands from xyyaw controls without any conflicts

Planned updates for MARSIM v1.2

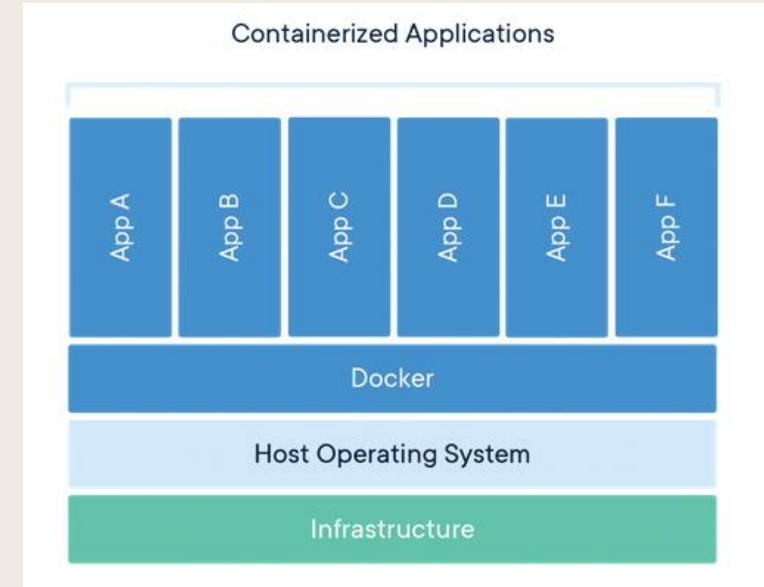
- marsim_gazebo
 - Add EKF with imu, dvl and depth sensors for models/sst
- marsim_control
 - Add displacement request and position hold for bluerov2 and sst

Agenda

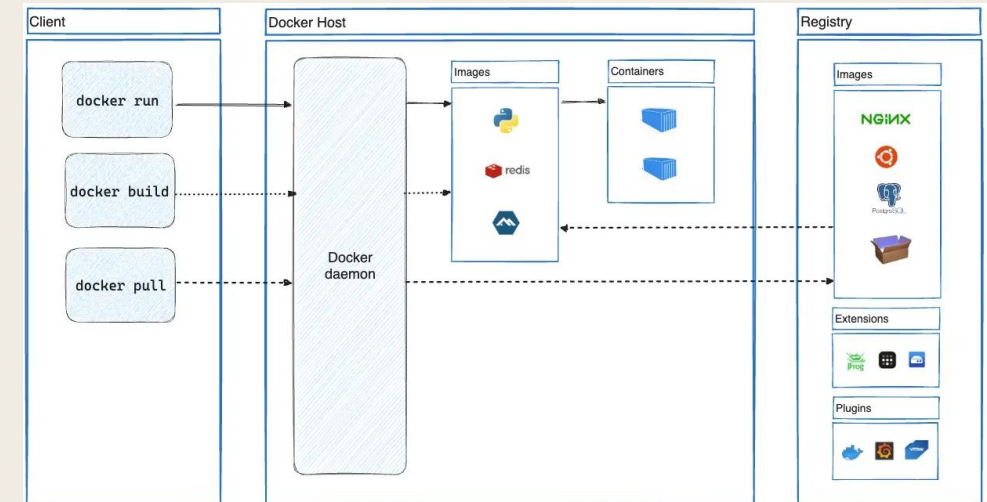
- Docker Engine
- ROS 2
- Gazebo
- Marine Simulator Gazebo (marsim_gazebo) package
- Marine Simulator Control (marsim_control) package

Docker Engine

- Open-source containerization tool
- Docker container:
 - Run-time environment with the applications to be run and their dependencies
- Docker image:
 - Standalone and executable file that is used to create the container
 - Contains all files required (application, libraries, dependencies, etc.)
 - Sharable and portable



Source: <https://www.docker.com/resources/what-container/>



Source: <https://docs.docker.com/guides/docker-overview/#docker-architecture>

Docker workflow process

- Step 1: Build the Docker image (Dockerfile)
 - Use a Dockerfile for easier definition of the image to be built
- Step 2: Load the Docker image as a container (load_dock.sh)
 - This is the main terminal of the container. Exiting from this terminal will unload the container.
 - No files will be saved in the container upon unloading.
 - Load and use a share volume from the host machine for saving work files.
- Step 3: Access the running Docker container if more additional terminals are required (access_cont.sh)
- Step 4: Exit from the container
 - Exiting from the main terminal will unload the container

DockerFile

○ Base image

- Example: nvidia/cuda:12.6.1-base-ubuntu24.04
- <https://hub.docker.com/r/nvidia/cuda>
- Reason: I am using a laptop that has NVIDIA RTX 2000 Ada. The Cuda base image has already many of the required graphics drivers pre-installed and configured.

○ Install packages

- Sudo not required; the build process runs in root
- Install ROS 2 jazzy, Gazebo harmonic, Gazebo/ROS pairing, misc ROS 2 tools and misc tools

```
Dockerfile > ...
1 # ----- Define base image -----
2 FROM nvidia/cuda:12.6.1-base-ubuntu24.04
3
4 # ----- Define environmental variables -----
5 ENV HOME=/home
6 ENV TZ=Europe/Oslo
7 RUN ln -snf /usr/share/zoneinfo/$TZ /etc/localtime && echo $TZ > /etc/timezone
8
9 # ----- Install ROS2 Jazzy -----
10 RUN apt update && apt install -y locales
11 RUN locale-gen en_US en_US.UTF-8
12 RUN update-locale LC_ALL=en_US.UTF-8 LANG=en_US.UTF-8
13 ENV LANG=en_US.UTF-8
14 RUN apt install -y software-properties-common
15 RUN add-apt-repository universe
16 RUN apt update && apt install curl -y
17 RUN curl -sSL https://raw.githubusercontent.com/ros/rosdistro/master/ros.key -o /usr/share/keyrings/ros-archive-keyring.gpg
18 RUN echo "deb [arch=$(dpkg --print-architecture) signed-by=/usr/share/keyrings/ros-archive-keyring.gpg] http://packages.ros.org/ros-archive/ubuntu jammy main" > /etc/apt/sources.list.d/ros-list.txt
19 RUN apt update && apt install -y ros-dev-tools
20 RUN apt update -y && apt upgrade -y
21 RUN apt install -y ros-jazzy-desktop
22 RUN echo "source /opt/ros/jazzy/setup.bash" >> ~/.bashrc
23
24 # ----- Install Gazebo Harmonic -----
25 RUN apt-get update
26 RUN apt-get install -y lsb-release gnupg
27 RUN curl https://packages.osrfoundation.org/gazebo.gpg --output /usr/share/keyrings/gazebo-archive-keyring.gpg
28 RUN echo "deb [arch=$(dpkg --print-architecture) signed-by=/usr/share/keyrings/gazebo-archive-keyring.gpg] http://packages.osrfoundation.org/gazebo/ubuntu-jammy main" > /etc/apt/sources.list.d/gazebo-list.txt
29 RUN apt-get update
30 RUN apt-get install -y gz-harmonic
31
32 # ----- Install Gazebo/ROS pairing -----
33 RUN apt-get install -y ros-jazzy-ros-gz
```

Load and run Docker container

○ load_dock.sh

- **xhost +local:docker**: Allows the Docker container to access the host's X server for GUI applications.
- Container options: **-it**: Interactive mode with a pseudo-TTY; **--rm**: Automatically remove the container when it exits; **--privileged**: Gives extended privileges to this container; **--gpus all**: Allows the container to use all available NVIDIA GPUs; **--name marsim_sdf_cont**: Names the container "marsim_sdf_cont".
- Environment variables: **XDG_RUNTIME_DIR=/tmp/runtime-root**: Sets the runtime directory; **DISPLAY=\$DISPLAY**: Passes the host's DISPLAY environment to the container; **QT_X11_NO_MITSHM=1**: Disables MIT-SHM extension for Qt applications; **MESA_GL_VERSION_OVERRIDE=3.3**: Forces OpenGL version 3.3 for Mesa drivers.
- Volume mounts: **/tmp/.X11-unix:/tmp/.X11-unix**: Mounts X11 socket for GUI support; **/home/yhxing/Docker_WS/marsim1:/home/marsim_ws:rw**: Mounts a local directory into the container with read-write access;
- **--runtime=nvidia**: Specifies to use the NVIDIA Container Runtime.

○ access_cont.sh

load_dock.sh

```
$ load_dock.sh
1  #!/usr/bin/bash
2
3  xhost +local:docker
4
5  docker run \
6  -it --rm \
7  --privileged \
8  --gpus all \
9  --name marsim_cont \
10 --env="XDG_RUNTIME_DIR=/tmp/runtime-root" \
11 --env="DISPLAY=$DISPLAY" \
12 --env="QT_X11_NO_MITSHM=1" \
13 --env="MESA_GL_VERSION_OVERRIDE=3.3" \
14 --volume="/tmp/.X11-unix:/tmp/.X11-unix" \
15 --volume="/home/yhxing/Docker_WS/marsim1:/home/marsim_ws:rw" \
16 --runtime=nvidia \
17 marsim1_dock
```

access_cont.sh

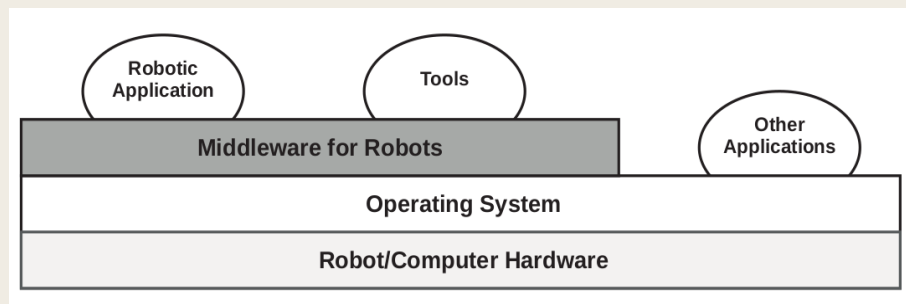
```
$ access_dock.sh
1  #!/usr/bin/bash
2
3  docker exec -it marsim_sdf_cont /bin/bash
```

Some notes on load_dock.sh











- If you do not have a Nvidia GPU on your host machine, remove --gpus all and --runtime=nvidia
- Remember to change the volume mounting of the workspace directory to your own workspace directory

Robot Operating System 2 (ROS 2)

- Material is taken from Rico, F. M. (2022). A concise introduction to robot programming with ROS 2. Chapman and Hall/CRC.
- ROS 2 is not an operating system; it is a middleware developed and maintained by the Open Robotics Foundation
- Middleware is a layer of software between the operating system and the user applications
- ROS 2 is the 2nd generation of ROS

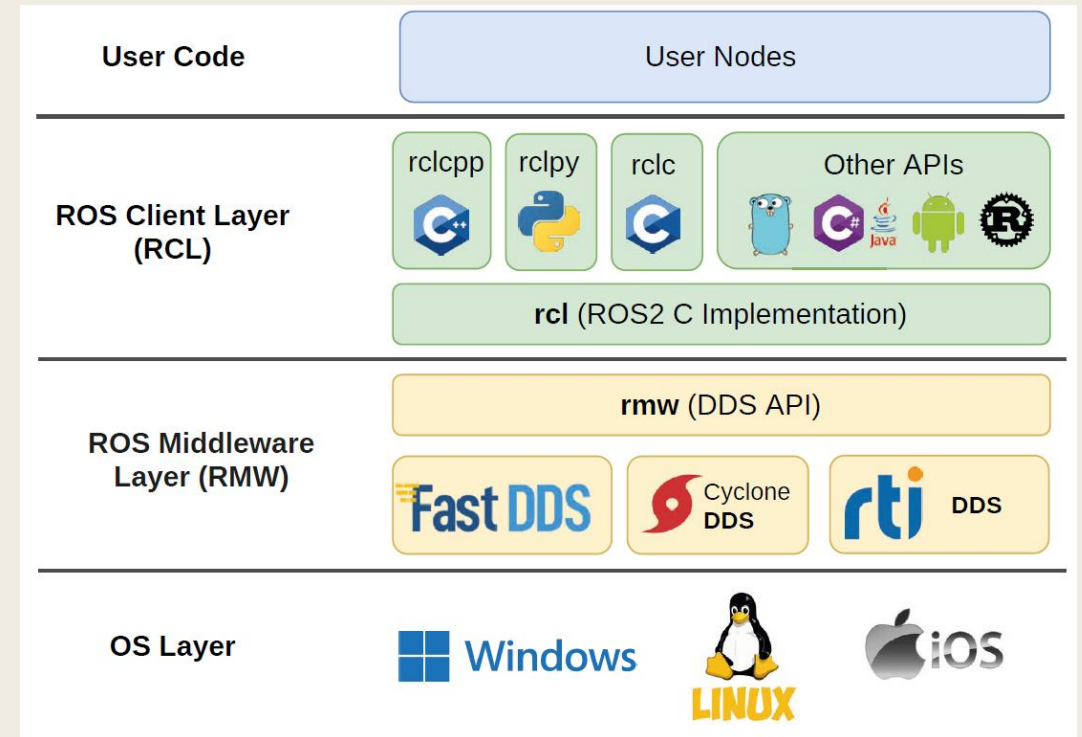


Source: Rico, F. M. (2022). A concise introduction to robot programming with ROS2. Chapman and Hall/CRC

Distro	Release date	Logo	EOL date
Jazzy Jalisco	May 23rd, 2024		May 2029
Iron Irtwin	May 23rd, 2023		November 2024
Humble Hawksbill	May 23rd, 2022		May 2027
Galactic Geochelone	May 23rd, 2021		December 9th, 2022
Foxy Fitzroy	June 5th, 2020		June 20th, 2023
Eloquent Elusor	November 22nd, 2019		November 2020
Dashing Diademata	May 31st, 2019		May 2021
Crystal Clemmys	December 14th, 2018		December 2019
Bouncy Bolson	July 2nd, 2018		July 2019
Ardent Apalone	December 8th, 2017		December 2018

ROS 2 architecture

- User nodes interface with ROS 2 via RCL's APIs
- rcl is the core of ROS 2 and is written in C
- rclcpp, rclpy, rcl, etc binds different programming languages to rcl offering the same behaviour, i.e., they are not independent implementations
- ROS 2 is a distributed system using data distribution system (DDS) as its communications layer
- There are several DDS vendors; ROS 2 Humble uses Cyclone DDS



Source: Rico, F. M. (2022). A concise introduction to robot programming with ROS2. Chapman and Hall/CRC

ROS 2 vs ROS 1

○ Architecture

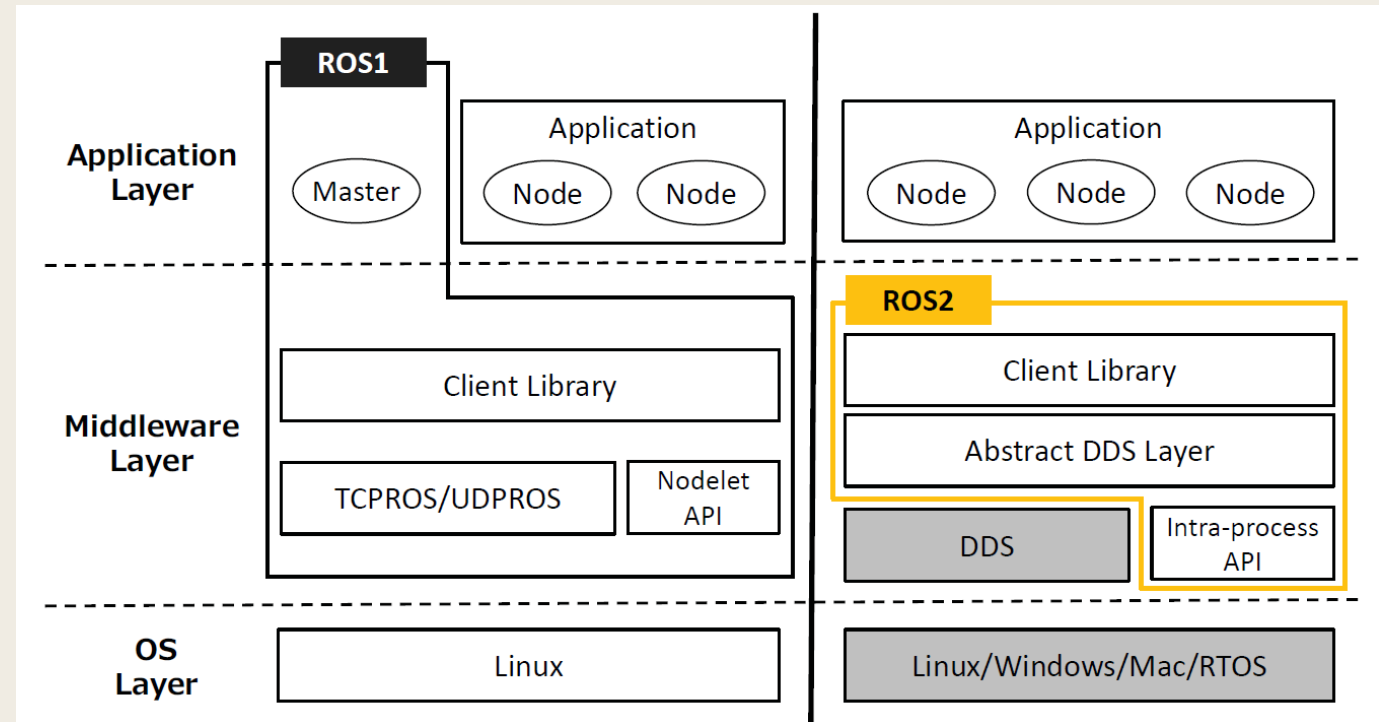
- DDS (ROS 2) vs Master-Slave Architecture and the XML-RPC middleware (ROS 1)
- rcp with binders to any programming language (ROS 2) vs two separate libraries roscpp and rospy (ROS 1)

○ Features

- QoS, multi-threaded execution and real-time processing

○ Tooling/Ecosystem

- Not backward compatible, but interface with ROS 1 can be done via ROSbridge



Maruyama, Y., Kato, S., & Azumi, T. (2016, October). Exploring the performance of ROS2. In Proceedings of the 13th international conference on embedded software (pp. 1-10).

Components of ROS 2

- ROS 2 is open source
- The community
 - Large community of users and developers contributing software packages
- Computation graph
 - ROS 2 runs as a computational graph consisting of nodes and arcs
- Workspace
 - This is the user workspace that consists of the set of software installed on the robot or computer and the programs that the user develops

The computational graph

- Node: single purpose executable program
- Topic: a named bus over which nodes exchange messages
- Publication/subscription: nodes sending/receiving messages on a topic
- Service: a synchronous request/response interaction between nodes: must be completed before the next one begins
- Action: an asynchronous request/response interaction with feedback; can be performed concurrently without waiting for each other to complete



Figure 1.3: Description of symbols used in computer graph diagrams.

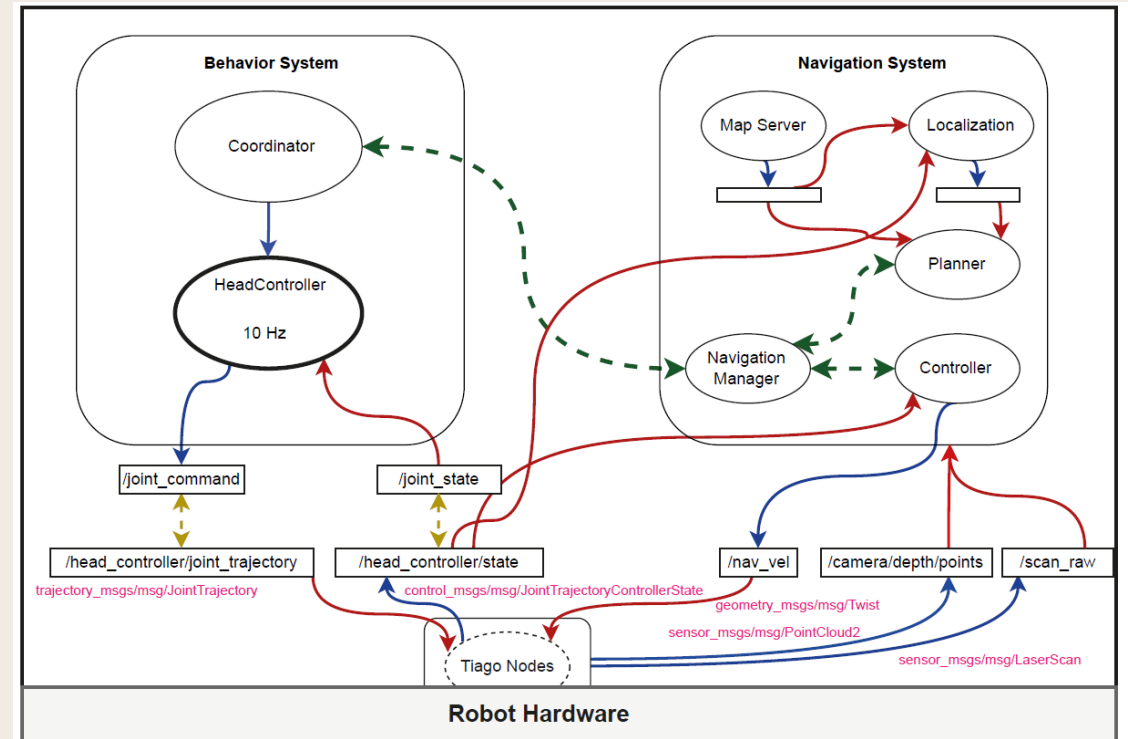
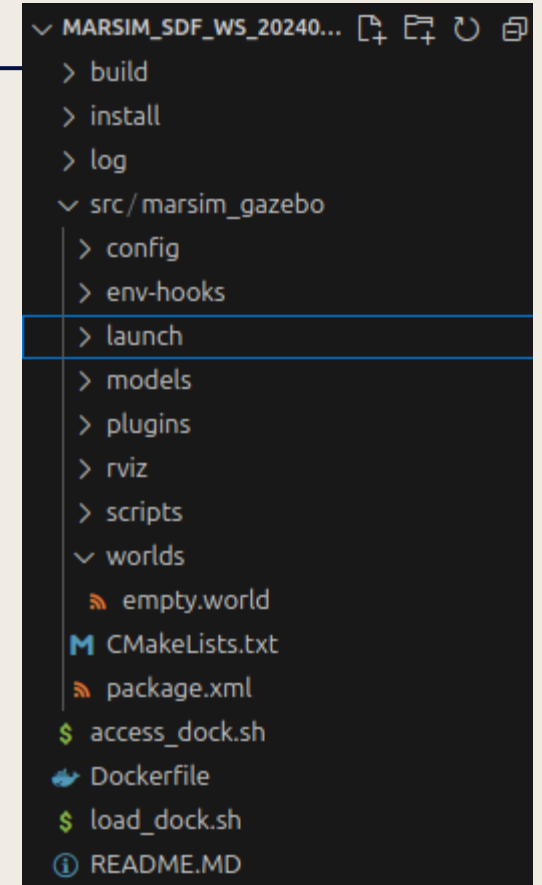


Figure 1.6: Computing graph of behavior-based application for the Tiago robot that uses a navigation subsystem.

Source: Rico, F. M. (2022). A concise introduction to robot programming with ROS2. Chapman and Hall/CRC

ROS 2 workspace

- Workspace directory
- Source code of user programs (packages) are stored in **src**
 - The workspace can contain multiple packages
 - Each package is stored in 1 directory with **CMakeList.txt** and **package.xml**
- Workspace needs to be built using **colcon build**
 - **build**, **install** and **log** directories are created
- To run the packages, the workspace needs to be sourced after building
 - **source install/setup.bash**



CMakeList.txt and package.xml

- Must be placed at the root of the package directory
- Defines the build tool, folders to be included, dependencies, etc

```
cmake_minimum_required(VERSION 3.5)
project(gritbot_description)

find_package(ament_cmake REQUIRED)
find_package(urdf REQUIRED)

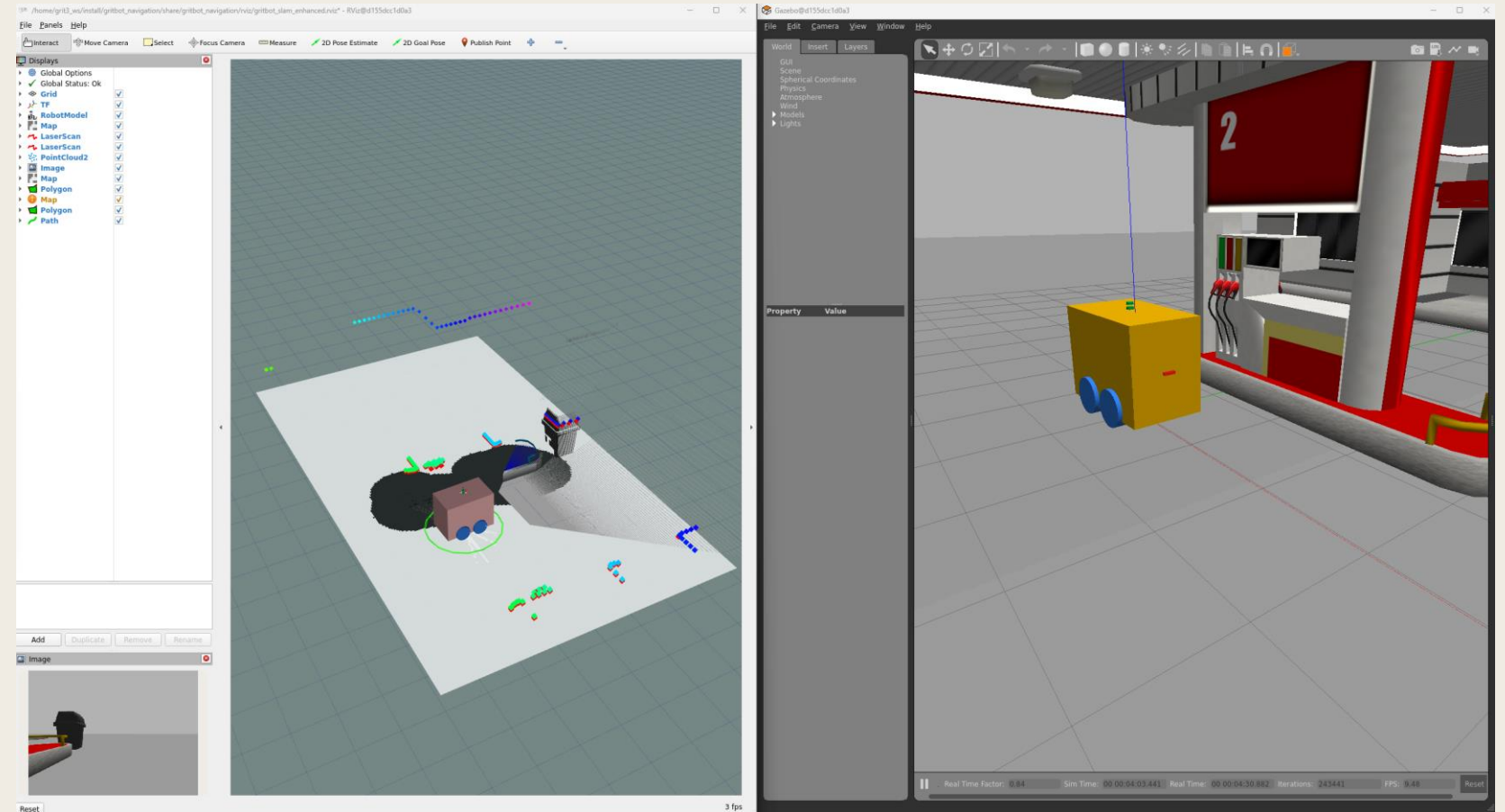
install(
  DIRECTORY launch urdf rviz
  DESTINATION share/${PROJECT_NAME}
)

ament_package()
```

```
<?xml version="1.0"?>
<?xml-model href="http://download.ros.org/schema/package_format3.xsd" schematypens="http://www.w3.org/2001/XMLSchema"?>
<package format="3">
  <name>gritbot_description</name>
  <version>0.0.0</version>
  <description>Gritbot Description Package</description>
  <maintainer email="yihan.xing@uis.no">Yihan Xing</maintainer>
  <license>Apache 2.0</license>
  <url type="website">TBA</url>
  <url type="repository">TBA</url>
  <url type="bugtracker">TBA</url>
  <buildtool_depend>ament_cmake</buildtool_depend>
  <exec_depend>joint_state_publisher</exec_depend>
  <exec_depend>robot_state_publisher</exec_depend>
  <exec_depend>rviz2</exec_depend>
  <exec_depend>xacro</exec_depend>
  <export>
    <build_type>ament_cmake</build_type>
  </export>
</package>
```

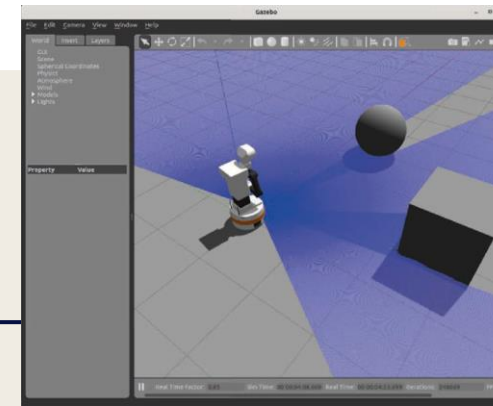
Rviz2

- Port of Rviz to ROS2
- Installed by ROS2 by default
- Provides graphic interface for users to view the robot, sensor data, maps, etc

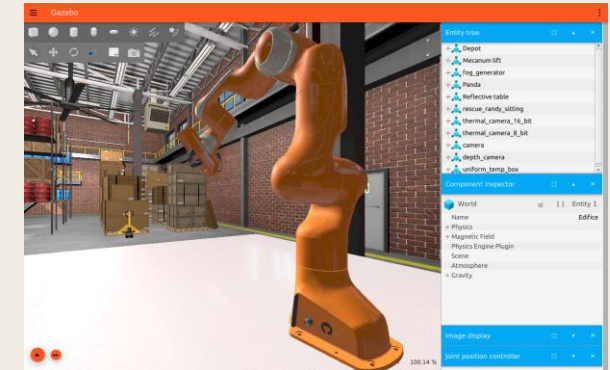


Gazebo

- Open-source 3D robotics simulator developed and maintained by the Open Robotics Foundation
- Commonly used together with ROS and ROS2
- Features:
 - Physics engines: e.g., ODE, Bullet, Simbody and DART
 - 3D graphics: uses Object-Oriented Graphics Rendering Engine
 - Sensors and actuators: e.g., lidar, IMU, cameras, GPS, etc
 - Plugins: easily extendable for custom functionalities
 - World and environment: allows for complex and dynamic environments
 - Multi-robot simulation
- Gazebo classic and Gazebo (previously Ignition Gazebo)
- We are using **Gazebo Harmonic**



Gazebo Classic. Source: Rico, F. M. (2022). A concise introduction to robot programming with ROS2. Chapman and Hall/CRC



Gazebo. Source: <https://github.com/gazebo/gazebo>

Feature	Gazebo Classic	Gazebo (Ignition Gazebo)
Maturity	Established, widely adopted	Newer, growing ecosystem
Architecture	Monolithic	Modular
Performance	Good, but less optimized	Improved performance and scalability
Integration	Strong ROS 1 and ROS 2 support	Strong ROS 2 support
Plugins	Extensive, but less modular	Improved, modular plugins
Physics Engines	Multiple engines supported	Enhanced physics capabilities
Rendering	OGRE-based	Advanced rendering with modern APIs
Cross-Platform Support	Primarily Linux, limited Windows/macOS	Better cross-platform support
Development	Stable, less active development	Actively developed and growing

ros_gz_bridge

- A network bridge which enables the exchange of messages between ROS 2 and Gazebo Transport
- We need a bridge because the robot is simulated in Gazebo, while the robot is controlled in ROS2; the messages of the robot from Gazebo must be ported to ROS2
- Limited to only certain message types
- There are several ways to configure the bridge; we will use a yaml file, which is the easiest way

```
src > marsim_gazebo > config > ! bluerov2_ros_gz_bridge.yaml
1  - ros_topic_name: "clock"
2    gz_topic_name: "clock"
3    ros_type_name: "rosgraph_msgs/msg/Clock"
4    gz_type_name: "gz.msgs.Clock"
5    subscriber_queue: 10      # Default 10
6    publisher_queue: 10      # Default 10
7    lazy: true                # Default "false"
8    direction: GZ_TO_ROS     # Default "BIDIRECTIONAL" - Bridge both directions
9                                # "GZ_TO_ROS" - Bridge Gz topic to ROS
10                               # "ROS_TO_GZ" - Bridge ROS topic to Gz
11
12 - ros_topic_name: "/bluerov2/ocean_current"
13   gz_topic_name: "/model/bluerov2/ocean_current"
14   ros_type_name: "geometry_msgs/msg/Vector3"
15   gz_type_name: "gz.msgs.Vector3d"
16   subscriber_queue: 10      # Default 10
17   publisher_queue: 10      # Default 10
18   lazy: true                # Default "false"
19   direction: GZ_TO_ROS     # Default "BIDIRECTIONAL" - Bridge both directions
20                               # "GZ_TO_ROS" - Bridge Gz topic to ROS
21                               # "ROS_TO_GZ" - Bridge ROS topic to Gz
22
23 - ros_topic_name: "/bluerov2/joint_states"
24   gz_topic_name: "/world/ocean/model/bluerov2/joint_state"
25   ros_type_name: "sensor_msgs/msg/JointState"
26   gz_type_name: "gz.msgs.Model"
27   subscriber_queue: 10      # Default 10
28   publisher_queue: 10      # Default 10
29   lazy: true                # Default "false"
30   direction: GZ_TO_ROS     # Default "BIDIRECTIONAL" - Bridge both directions
31                               # "GZ_TO_ROS" - Bridge Gz topic to ROS
32                               # "ROS_TO_GZ" - Bridge ROS topic to Gz
33
```


Marine Simulator Gazebo (marsim_gazebo) package

- World
 - Standard Gazebo physics, user commands, scene broadcaster, imu, sensors, dvl system and buoyancy plugins
 - Seabed modelling using a heightmap model
 - Custom-written Gauss Markov ocean current plugin
- Currently only BlueROV2 model - main body with 6 thrusters
 - Buoyancy modelled using a rectangular collision geometry
 - Standard Gazebo hydrodynamic, joint state publisher, pose publisher and odometry publisher plugins
 - Thruster attached to main body using revolute joints with standard Gazebo thruster plugins
 - Standard Gazebo IMU and DVL sensors with a custom-written ccp plugins and python scripts for post processing of measurements
 - Simulated depth sensor using standard Gazebo odometry publisher with added noise using a custom-written python script
 - ROS2 robot description and robot localization packages
 - Custom-written python script for robot keyboard controller

Custom-written plugins and scripts

- Source codes are stored in /plugins and /scripts
- marsim_gazebo::GaussMarkovOceanCurrent
- marsim_gazebo::DVLRosConverter
- depth_sensor_from_odom.py
- noisy_odometry.py
- ros_keyboard_controller.py
- twist_stamper.py

marsim1.2 ROS 2-Gazebo model

- Currently only the **marsim_gazebo** package
- **config**: holds the configuration files such as the `roz_gz_bridge` yaml file
- **env-hooks**: holds the files required to define paths
- **launch**: holds the python launch files
- **models**: holds folders which contain the models in sdf format
- **plugins**: holds the cpp source codes (cc and hh files) for custom-made Gazebo plugins
- **rviz**: holds the Rviz2 configuration yaml files
- **scripts**: holds scripts that can be used to control the BlueROV2
- **worlds**: holds sdf world files

```
▼ MARSIM1
  ▼ src/marsim_gazebo
    > config
    > env-hooks
    > launch
    > models
    > plugins
    > rviz
    > scripts
    > worlds
    M CMakeLists.txt
    ≡ LICENSE-2.0.txt
    📄 package.xml
    $ access_dock.sh
    🐳 Dockerfile
    $ load_dock.sh
    ⓘ README.md
```

Starting up the model

- `ros2 launch marsim_gazebo empty_world.launch.py`
- `ros2 launch marsim_gazebo spawn_bluerov2.launch.py`
- `ros2 launch marsim_gazebo start_bridge.launch.py`
- `ros2 launch marsim_gazebo complete_simlaunch_bluerov2.launch.py`
- `ros run marsim_gazebo ros_keyboard_controller bluerov2`

ROS2-GZ bridge

- We need a bridge because ROS2 and Gazebo are separate programs
- Recap:
 - ROS2 (Robot Operating System 2):
 - A flexible framework for writing robot software
 - Provides a collection of tools, libraries, and conventions for robot development
 - Handles communication between different parts of a robotic system
 - Supports multiple programming languages (C++, Python, etc.)
 - Designed for distributed computing and real-time systems
 - Used for both simulated and physical robots
 - Gazebo:
 - A 3D dynamic simulator for robots
 - Provides accurate simulation of robots in complex indoor and outdoor environments
 - Offers realistic sensor feedback and physically plausible interactions
 - Can simulate multiple robots
 - Often used in conjunction with ROS/ROS2 for testing and development

ROS 2-GZ bridge

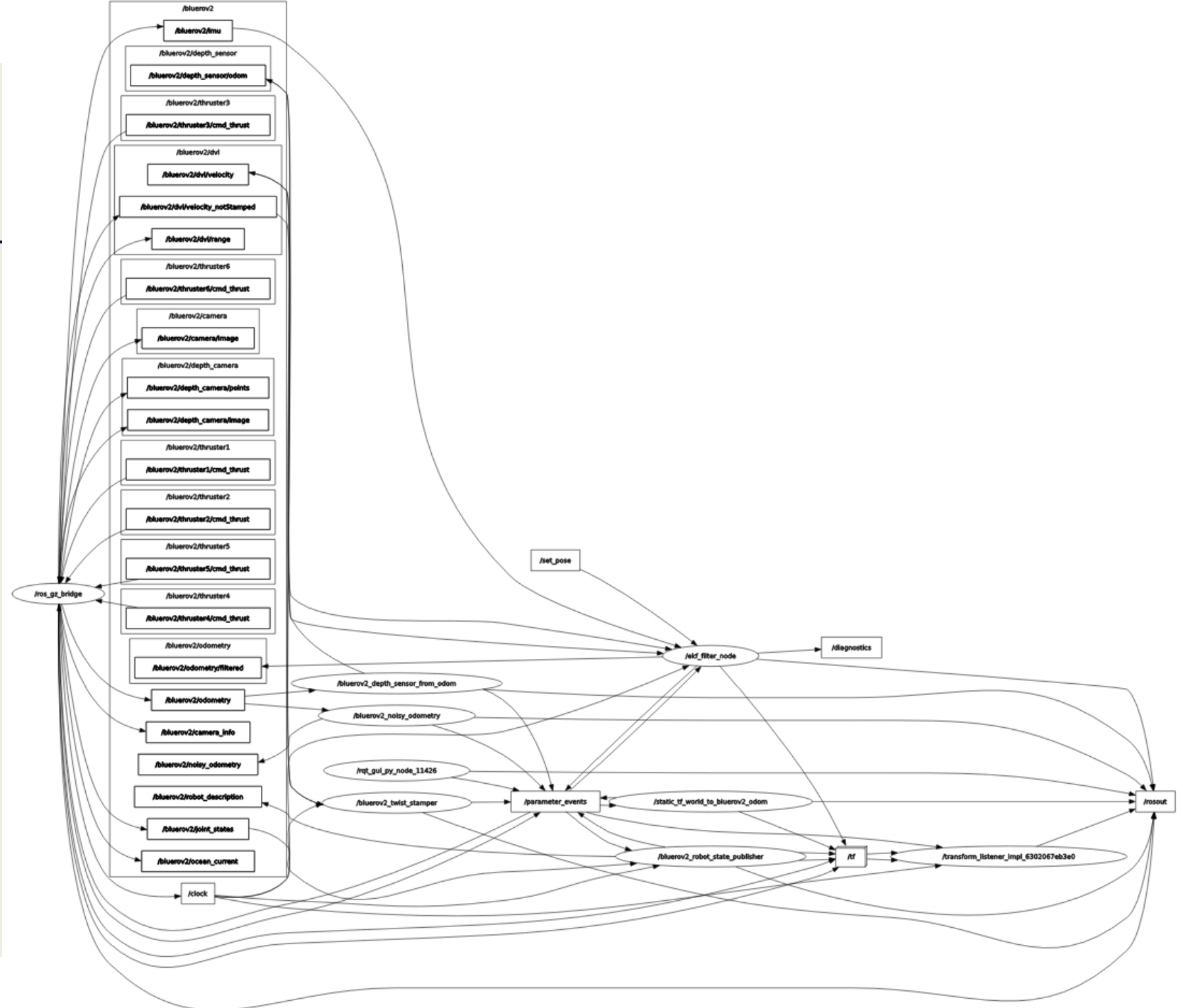
- Configured using bluerov2_ros_gz_bridge.yaml
- Gazebo is the simulator, and ROS2 is the robot computer
- Environment and robot measurements: Gazebo ---> ROS2
- Robot commands: ROS2 ---> Gazebo

```
src > marsim_gazebo > config > ! bluerov2_ros_gz_bridge.yaml
1 - ros_topic_name: "clock"
2   gz_topic_name: "clock"
3   ros_type_name: "rosgraph_msgs/msg/Clock"
4   gz_type_name: "gz.msgs.Clock"
5   subscriber_queue: 10      # Default 10
6   publisher_queue: 10      # Default 10
7   lazy: true                # Default "false"
8   direction: GZ_TO_ROS     # Default "BIDIRECTIONAL" - Bridge both directions
9                             # "GZ_TO_ROS" - Bridge Gz topic to ROS
10                            # "ROS_TO_GZ" - Bridge ROS topic to Gz
11
12 - ros_topic_name: "/bluerov2/ocean_current"
13   gz_topic_name: "/model/bluerov2/ocean_current"
14   ros_type_name: "geometry_msgs/msg/Vector3"
15   gz_type_name: "gz.msgs.Vector3d"
16   subscriber_queue: 10      # Default 10
17   publisher_queue: 10      # Default 10
18   lazy: true                # Default "false"
19   direction: GZ_TO_ROS     # Default "BIDIRECTIONAL" - Bridge both directions
20                             # "GZ_TO_ROS" - Bridge Gz topic to ROS
21                             # "ROS_TO_GZ" - Bridge ROS topic to Gz
22
23 - ros_topic_name: "/bluerov2/joint_states"
24   gz_topic_name: "/world/ocean/model/bluerov2/joint_state"
25   ros_type_name: "sensor_msgs/msg/JointState"
26   gz_type_name: "gz.msgs.Model"
27   subscriber_queue: 10      # Default 10
28   publisher_queue: 10      # Default 10
29   lazy: true                # Default "false"
30   direction: GZ_TO_ROS     # Default "BIDIRECTIONAL" - Bridge both directions
31                             # "GZ_TO_ROS" - Bridge Gz topic to ROS
32                             # "ROS_TO_GZ" - Bridge ROS topic to Gz
33
```

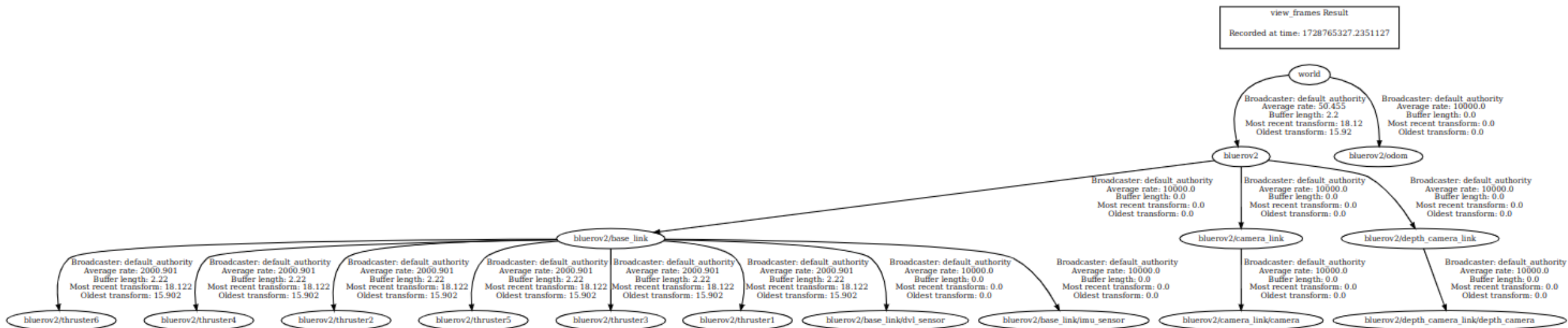
```
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating GZ->ROS Bridge: [clock (gz.msgs.Clock) -> clock (rosgraph_msgs/msg/Clock)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating GZ->ROS Bridge: [/model/bluerov2/ocean_current (gz.msgs.Vector3d) -> /bluerov2/ocean_current (geometry_msgs/msg/Vector3)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating GZ->ROS Bridge: [/world/ocean/model/bluerov2/joint_state (gz.msgs.Model) -> /bluerov2/joint_states (sensor_msgs/msg/JointState)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating GZ->ROS Bridge: [/model/bluerov2/pose (gz.msgs.Pose_V) -> /tf (tf2_msgs/msg/TFMessage)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating GZ->ROS Bridge: [/model/bluerov2/pose_static (gz.msgs.Pose_V) -> /tf_static (tf2_msgs/msg/TFMessage)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating GZ->ROS Bridge: [/model/bluerov2/odometry_with_covariance (gz.msgs.OdometryWithCovariance) -> /odometry (nav_msgs/msg/Odometry)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating GZ->ROS Bridge: [/model/bluerov2/imu (gz.msgs.IMU) -> /bluerov2/imu (sensor_msgs/msg/Imu)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating GZ->ROS Bridge: [/model/bluerov2/dvl_ros_compatible/velocity (gz.msgs.TwistWithCovariance) -> /bluerov2/dvl/velocity_notStamped (geometry_msgs/msg/TwistWithCovariance)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating GZ->ROS Bridge: [/model/bluerov2/dvl_ros_compatible/range (gz.msgs.Float) -> /bluerov2/dvl/range (std_msgs/msg/Float32)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating ROS->GZ Bridge: [/bluerov2/thruster1/cmd_thrust (std_msgs/msg/Float64) -> /model/bluerov2/joint/thruster1_joint/cmd_thrust (gz.msgs.Double)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating ROS->GZ Bridge: [/bluerov2/thruster2/cmd_thrust (std_msgs/msg/Float64) -> /model/bluerov2/joint/thruster2_joint/cmd_thrust (gz.msgs.Double)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating ROS->GZ Bridge: [/bluerov2/thruster3/cmd_thrust (std_msgs/msg/Float64) -> /model/bluerov2/joint/thruster3_joint/cmd_thrust (gz.msgs.Double)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating ROS->GZ Bridge: [/bluerov2/thruster4/cmd_thrust (std_msgs/msg/Float64) -> /model/bluerov2/joint/thruster4_joint/cmd_thrust (gz.msgs.Double)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating ROS->GZ Bridge: [/bluerov2/thruster5/cmd_thrust (std_msgs/msg/Float64) -> /model/bluerov2/joint/thruster5_joint/cmd_thrust (gz.msgs.Double)] (Lazy 1)
[parameter_bridge-1] [INFO] [ros_gz_bridge]: Creating ROS->GZ Bridge: [/bluerov2/thruster6/cmd_thrust (std_msgs/msg/Float64) -> /model/bluerov2/joint/thruster6_joint/cmd_thrust (gz.msgs.Double)] (Lazy 1)
```

rqt_graph

- Namespace: bluerov2
- Important nodes
 - /ros_gz_bridge
 - /ekf_filter
 - /robot_state_publisher
 - /depth_sensor_from_odom
 - /noisy_odometry
 - /twist_stamper
- Important topics
 - /bluerov2
 - /tf
 - /robot_description
 - odometry
 - odometry/filtered



TF2 tree



- No bluerov2/base_link/depth_sensor because the depth sensor is simulated using pose z measurements from /odometry with gaussian noise added

EKF – Robot Localization package

- Implemented using ROS 2 robot localization package
- Configured using `bluerov2_ekf_config.yaml`
- imu0: standard Gazebo IMU sensor
 - Orientations, angular velocities, linear accelerations
- twist0
 - Linear velocities
- odom0
 - Only pose z
- Can be tuned through the definition of the covariances

EKF - Introduction

- Purpose: State estimation for nonlinear systems
 - Estimates the state of a dynamic system from noisy measurements
 - Crucial for robotics, autonomous systems, and control applications
- Extends the linear Kalman Filter to nonlinear systems
 - Uses local linearization around the current state estimate
- Key applications:
 - Robot localization and navigation
 - Sensor fusion in autonomous vehicles
 - Spacecraft attitude determination
 - Target tracking in radar systems
- Addresses challenges of:
 - System nonlinearity
 - Measurement and process noise
 - Multi-sensor integration

EKF algorithm

- The EKF algorithm aims to estimate the full 3D pose and velocity (6 pose states and 6 velocity states) of the robot over time
- Consists of two steps: prediction and update
- For more details, see Moore, T., & Stouch, D. (2016). A generalized extended kalman filter implementation for the robot operating system. In Intelligent Autonomous Systems 13: Proceedings of the 13th International Conference IAS-13 (pp. 335-348). Springer International Publishing.

EKF algorithm – Robot state and measurements

- Robot state: $\mathbf{x}_k = f(\mathbf{x}_{k-1}) + \mathbf{w}_{k-1}$
 - \mathbf{x}_k is the 12-dimensional state vector (x, y, z, roll, pitch, yaw, vx, vy, vz, wx, wy, wz) at time k
 - f is the nonlinear state transition function
 - \mathbf{w}_{k-1} is the process noise at time $k-1$ which is assumed to be normally distributed
- Measurements: $\mathbf{z}_k = h(\mathbf{x}_k) + \mathbf{v}_k$
 - \mathbf{z}_k is the measurement at time k
 - h is the nonlinear sensor model that maps the states into the measurement space
 - \mathbf{v}_k is the normally distributed sensor noise

EKF algorithm – Prediction step

- Project the current state estimate and error covariance forward in time:
- State prediction: $\text{est}(\mathbf{x}_k) = f(\mathbf{x}_{k-1})$
 - $\text{est}(\mathbf{x}_k)$ is the estimate of the state at time k
 - f is robot model or nonlinear state transition function
 - \mathbf{x}_{k-1} is the state at time $k-1$
- Covariance prediction: $\text{est}(\mathbf{P}_k) = \mathbf{F}\mathbf{P}_{k-1}\mathbf{F}^T + \mathbf{Q}$
 - $\text{est}(\mathbf{P}_k)$ is the estimated error covariance projected via \mathbf{F} and perturbed by \mathbf{Q}
 - \mathbf{F} is the Jacobian of f
 - \mathbf{Q} is the process noise covariance

EKF algorithm – Correction step

- Kalman gain calculation: $\mathbf{K} = \text{est}(\mathbf{P}_k) \mathbf{H}^T (\mathbf{H} \text{est}(\mathbf{P}_k) \mathbf{H}^T + \mathbf{R})^{-1}$
 - \mathbf{K} is the Kalman gain
 - \mathbf{H} is the observation matrix, the Jacobian of h , the observation model function or the nonlinear sensor model. To support a wide array of sensors, \mathbf{H} is an identity matrix in the robot_localization package.
 - \mathbf{R} is the measurement covariance
- State update: $\mathbf{x}_k = \text{est}(\mathbf{x}_k) + \mathbf{K}(\mathbf{z} - \mathbf{H} \text{est}(\mathbf{x}_k))$
- Covariance update: $\mathbf{P}_k = (\mathbf{I} - \mathbf{K}\mathbf{H}) \text{est}(\mathbf{P}_k) (\mathbf{I} - \mathbf{K}\mathbf{H})^T + \mathbf{K}\mathbf{R}\mathbf{K}^T$

EKF algorithm – Prediction step (more explanations)

- State prediction: $\text{est}(\mathbf{x}_k) = f(\mathbf{x}_{k-1})$
 - This equation projects the state estimate forward in time
 - f represents the robot's motion model. For example, if the robot is moving at a certain velocity, f would use this information to predict where the robot will be at the next time step.
 - The key point here is that f can be nonlinear, which is what distinguishes the Extended Kalman Filter from the regular Kalman Filter. This allows it to handle more complex systems and motions.

EKF algorithm – Prediction step (more explanations) (2)

- Covariance prediction: $\text{est}(\mathbf{P}_k) = \mathbf{F}\mathbf{P}_{k-1}\mathbf{F}^T + \mathbf{Q}$
 - \mathbf{F} is the Jacobian of f and represents how changes in the previous state affect the current state. It's used to transform the previous covariance into the new time step. The use of the Jacobian \mathbf{F} is another key aspect of the Extended Kalman Filter. It's a linear approximation of how the nonlinear function f behaves near the current estimate. This linearization is what allows the EKF to apply the Kalman Filter framework to nonlinear systems.
 - $\mathbf{F}\mathbf{P}_{k-1}\mathbf{F}^T$ propagates the previous uncertainty through the state transition model.
 - \mathbf{Q} adds additional uncertainty due to imperfections in our model or external factors we can't account for.

EKF algorithm – Correction step (more explanations)

- Kalman gain calculation: $\mathbf{K} = \text{est}(\mathbf{P}_k) \mathbf{H}^T (\mathbf{H} \text{est}(\mathbf{P}_k) \mathbf{H}^T + \mathbf{R})^{-1}$
 - $\text{est}(\mathbf{P}_k) \mathbf{H}^T$ represents how much we expect the measurement to change based on changes in our state estimate
 - $\mathbf{H} \text{est}(\mathbf{P}_k) \mathbf{H}^T + \mathbf{R}$ represents the total expected variance in our measurement (predicted measurement uncertainty + actual measurement noise).
 - The inverse at the end turns this into a ratio - effectively, "how much should we trust this measurement compared to our prediction?"
- State update: $\mathbf{x}_k = \text{est}(\mathbf{x}_k) + \mathbf{K}(\mathbf{z} - \mathbf{H} \text{est}(\mathbf{x}_k))$
 - $\mathbf{z} - \mathbf{H} \text{est}(\mathbf{x}_k)$ is the difference between the actual measurement \mathbf{z} and what we expected to measure $\mathbf{H} \text{est}(\mathbf{x}_k)$. This is often called the "innovation" or "measurement residual".
 - We multiply this difference by \mathbf{K} to determine how much to adjust our prediction. If \mathbf{K} is large, we adjust our estimate more towards the new measurement. If \mathbf{K} is small, we trust our prediction more.

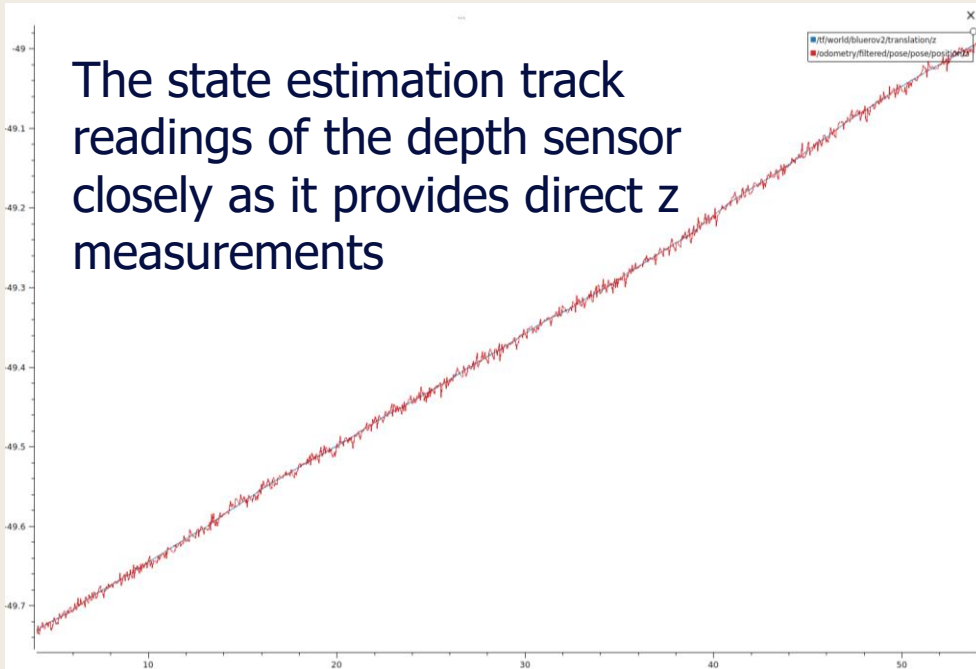
EKF algorithm – Correction step (more explanations) (2)

- Covariance update: $\mathbf{P}_k = (\mathbf{I} - \mathbf{KH}) \text{est}(\mathbf{P}_k)(\mathbf{I} - \mathbf{KH})^T + \mathbf{K}\mathbf{R}\mathbf{K}^T$
 - $\mathbf{I} - \mathbf{KH}$ represents how much of our previous uncertainty estimate we're keeping. If \mathbf{K} is large (we trusted the measurement a lot), this term becomes smaller.
 - $\text{est}(\mathbf{P}_k)(\mathbf{I} - \mathbf{KH})^T$ reduces our uncertainty based on how much information we gained from the measurement
 - $\mathbf{K}\mathbf{R}\mathbf{K}^T$ adds back some uncertainty based on how noisy our measurement was

State estimations of position z when different combination of sensors are used

Red line = estimated depth; Blue line = actual depth

IMU + DVL + Depth sensors



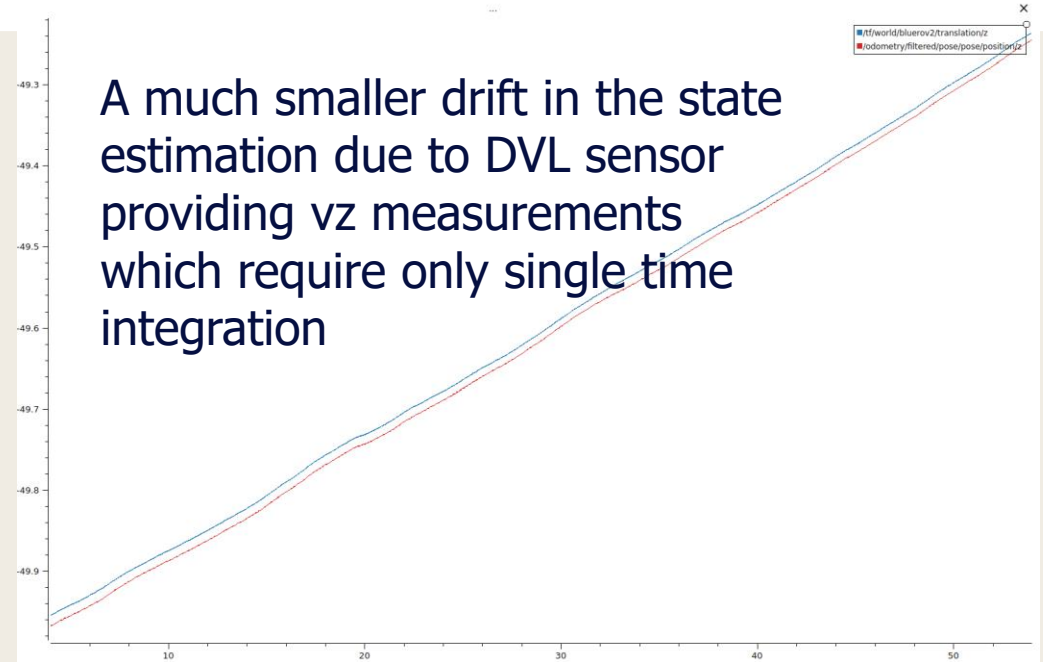
Measurements from the sensors:

IMU: $a_x, a_y, a_z, \omega_x, \omega_y, \omega_z$

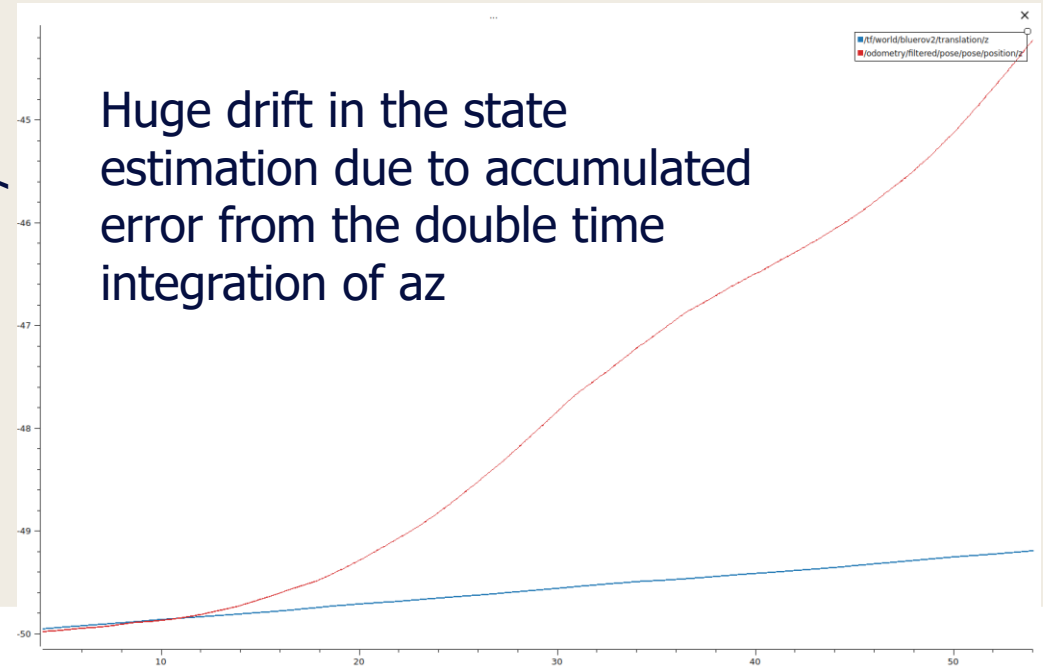
DVL: v_x, v_y, v_z

Depth: z

IMU + DVL sensors



IMU sensor only





Model Entity 20

- System Plugin Info
 - + JointStatePublisher
 - + PosePublisher
 - + OdometryPublisher
 - + DVLRosConverter
 - + Hydrodynamics
 - + Thruster
 - + Thruster
 - + Thruster
 - + Thruster
 - + Thruster
 - + Thruster

Name	bluerov2
Model	

Entity Tree +

- > water_plane
- > axes
- > sand_heightmap
- > sun
- ▼ bluerov2
 - ▼ base_link
 - base_link_visual
 - base_link_collision
 - imu_sensor
 - dvl_sensor
 - ▼ thruster1
 - thruster_prop_visual
 - > thruster2
 - > thruster3
 - > thruster4
 - > thruster5
 - > thruster6
 - thruster1_joint
 - thruster2_joint
 - thruster3_joint
 - thruster4_joint
 - thruster5_joint

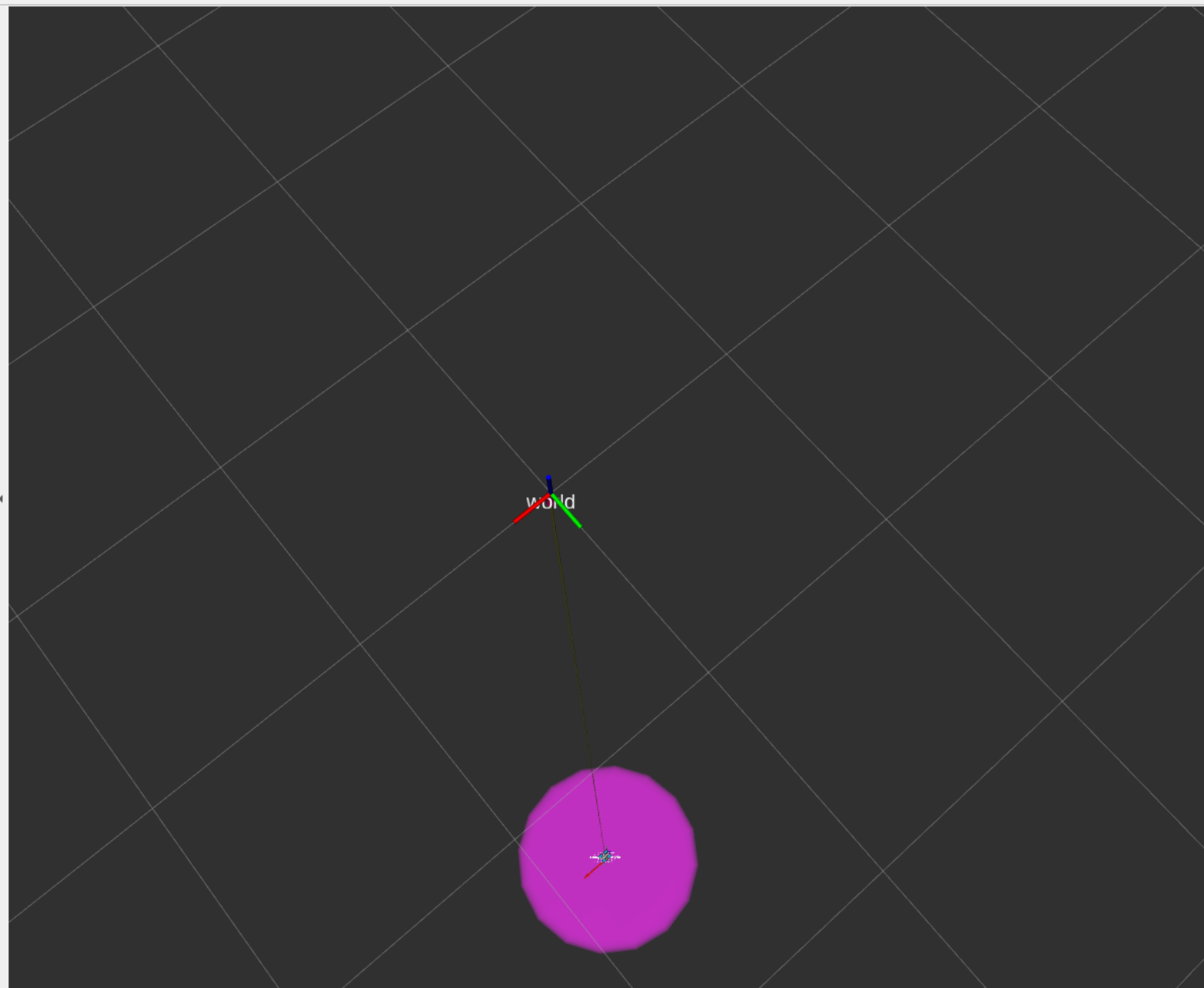
Displays

- Global Options
 - Fixed Frame: world
 - Background Color: 48; 48; 48
 - Frame Rate: 30
- Global Status: Ok
 - Fixed Frame: OK
- Grid: ☒
- RobotModel: ☒
 - Status: Ok
 - Visual Enabled: ☒
 - Collision Enabled: ☐
 - Mass Properties
 - Update Interval: 0
 - Alpha: 1
 - Description Source: Topic
 - Description Topic: /robot_description
 - TF Prefix: bluerov2
 - Links
- TF: ☒
 - Status: Ok
 - Show Names: ☒
 - Show Axes: ☒
 - Show Arrows: ☒
 - Marker Scale: 1
 - Update Interval: 0
 - Frame Timeout: 15
 - Filter (whitelist):
 - Filter (blacklist):
 - Frames
 - Tree
- Odometry: ☒

TF Prefix

Robot Model normally assumes the link name is the same as the tf frame name. This option allows you to set a prefix. Mainly useful for multi-robot situations.

Add Duplicate Remove Rename



Views

Type: Orbit (rviz_default_1) Zero

Current View

- Near Clip Di...: 0.01
- Invert Z Axis: ☐
- Target Frame: <Fixed Frame>
- Distance: 42.1307
- Focal Shape...: 0.05
- Focal Shape...: ☒
- Yaw: 0.867451
- Pitch: 1.24591
- Focal Point: -7.8417; -8.8489; -...

Save Remove Rename

File Panels Help

Interact Move Camera Select Focus Camera Measure 2D Pose Estimate 2D Goal Pose Publish Point + -

Displays

- Global Options
 - Fixed Frame world
 - Background Color 48; 48; 48
 - Frame Rate 30
- Global Status: Ok
 - Fixed Frame OK
- Grid
 - ☒
- RobotModel
 - ☒
 - Status: Ok
 - Visual Enabled ☒
 - Collision Enabled ☐
 - Mass Properties
 - Update Interval 0
 - Alpha 1
 - Description Source Topic
 - Description Topic /robot_description
 - TF Prefix bluerov2
 - Links
 - ☒
- TF
 - Status: Ok
 - Show Names ☒
 - Show Axes ☒
 - Show Arrows ☒
 - Marker Scale 1
 - Update Interval 0
 - Frame Timeout 15
 - Filter (whitelist)
 - Filter (blacklist)
 - Frames
 - Tree
- Odometry
 - ☒

TF Prefix

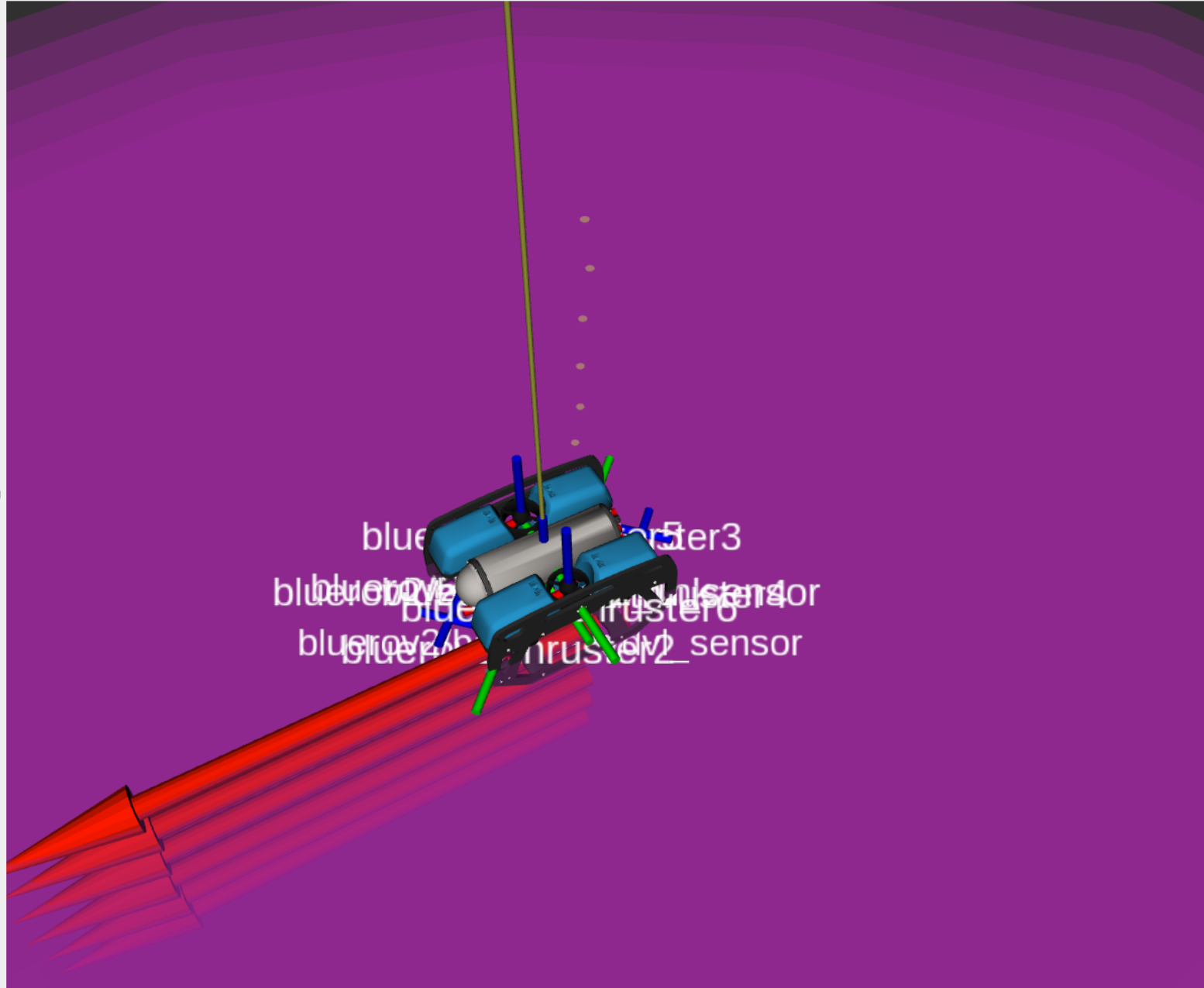
Robot Model normally assumes the link name is the same as the tf frame name. This option allows you to set a prefix. Mainly useful for multi-robot situations.

Add

Duplicate

Remove

Rename



Views

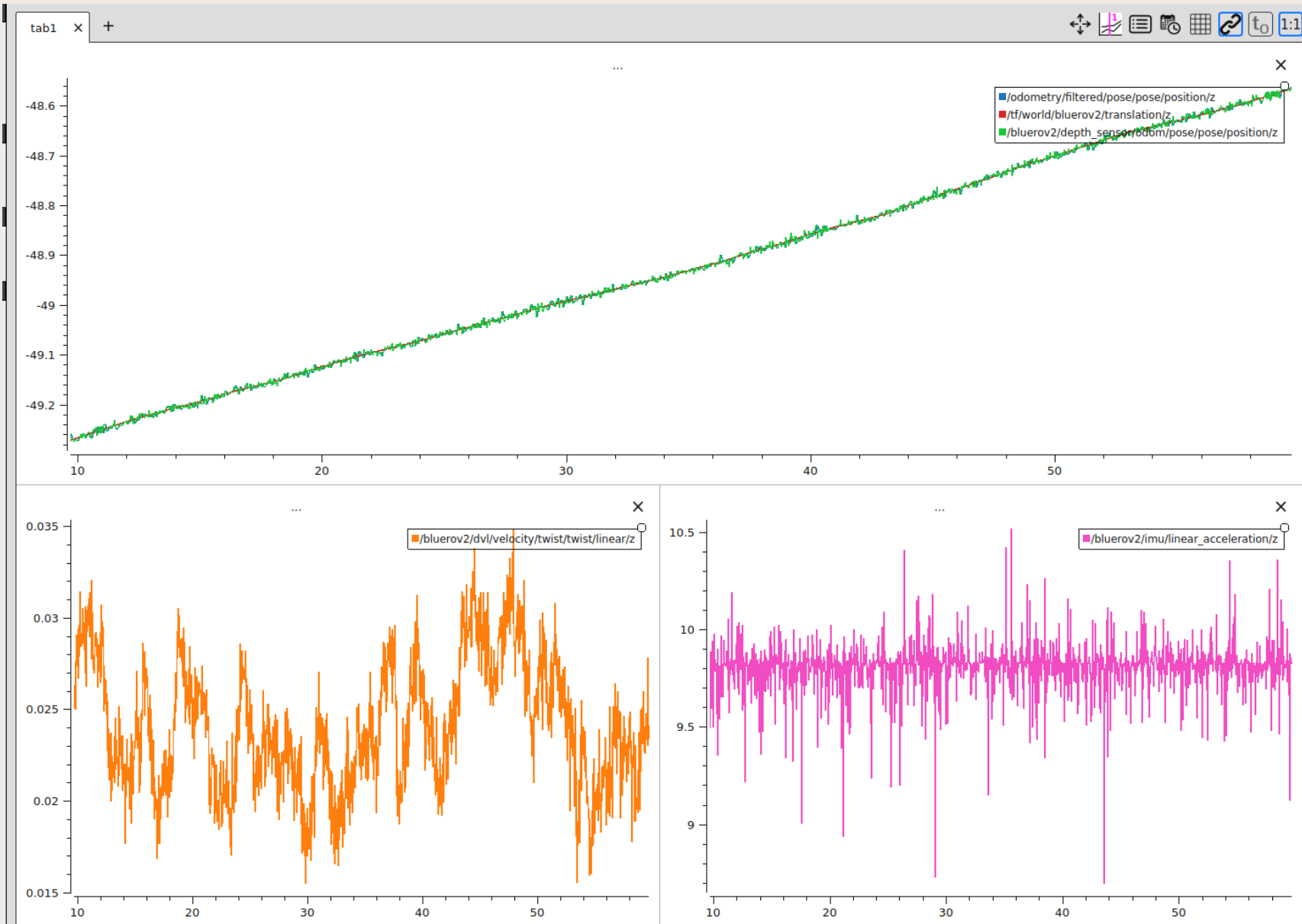
Type: Orbit (rviz_default_1) Zero

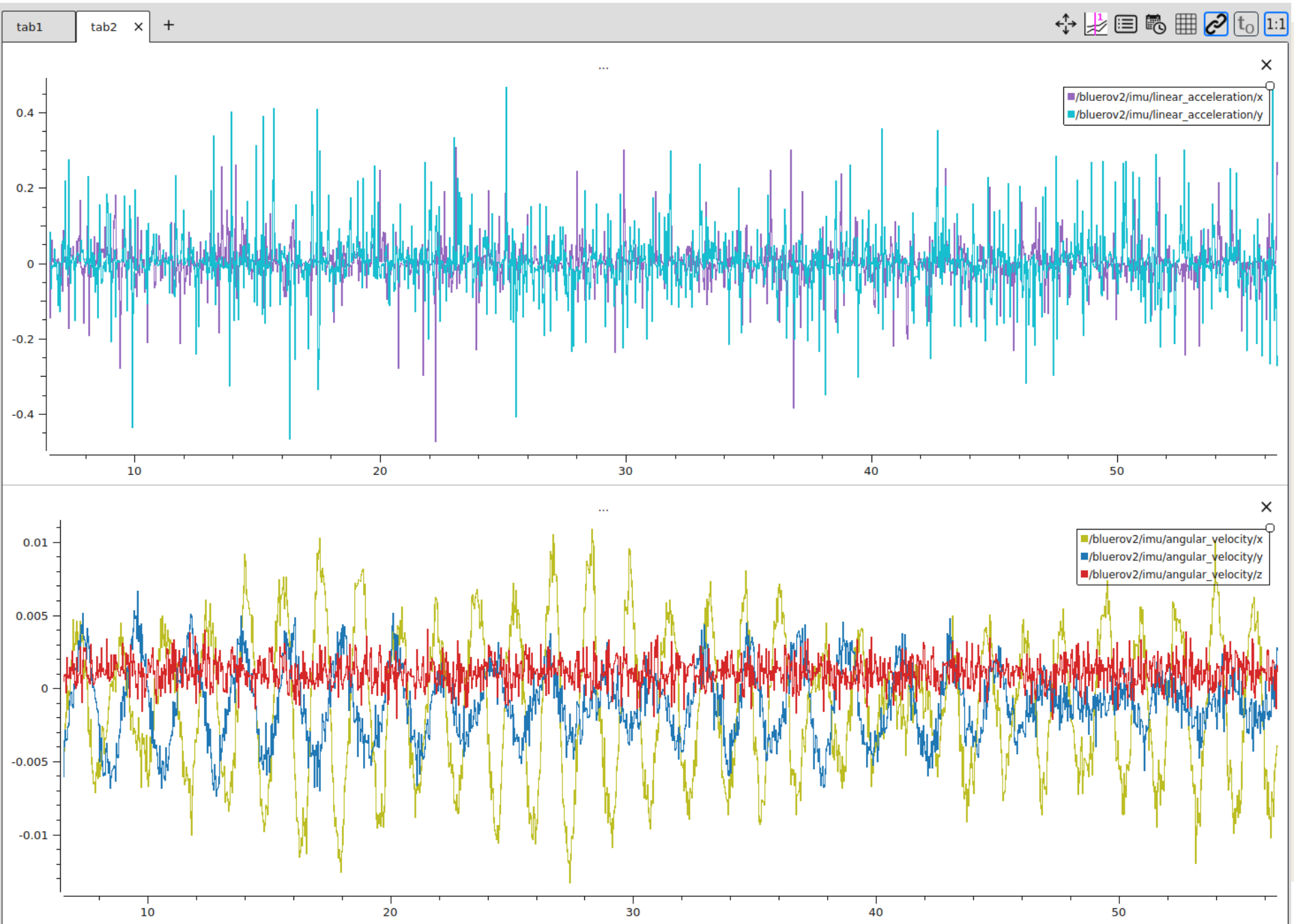
- Current View
 - Near Clip Di... 0.01
 - Invert Z Axis ☐
 - Target Frame <Fixed Frame>
 - Distance 1.67249
 - Focal Shape... 0.05
 - Focal Shape... ☒
 - Yaw 1.05745
 - Pitch 0.86591
 - Focal Point 0.1264; 0.49305; -...

Save

Remove

Rename



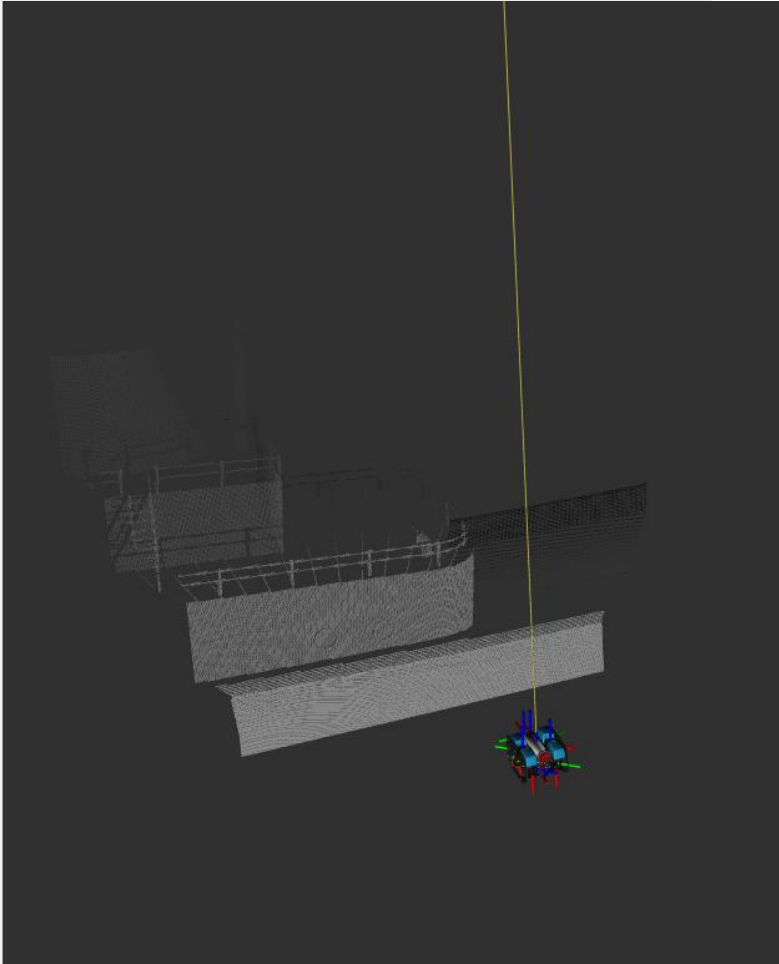


With camera and depth camera sensors



Collision Enabled	<input type="checkbox"/>
Mass Properties	
Update Interval	0
Alpha	1
Description Source	Topic
Description Topic	/bluerov2/robot_descripti...
TF Prefix	bluerov2
Links	
TF	<input checked="" type="checkbox"/>
Status: Ok	<input checked="" type="checkbox"/>
Show Names	<input type="checkbox"/>
Show Axes	<input checked="" type="checkbox"/>
Show Arrows	<input checked="" type="checkbox"/>
Marker Scale	1
Update Interval	0
Frame Timeout	15
Filter (whitelist)	
Filter (blacklist)	
Frames	
Tree	
Image	<input checked="" type="checkbox"/>
PointCloud2	<input checked="" type="checkbox"/>

Add Duplicate Remove Rename



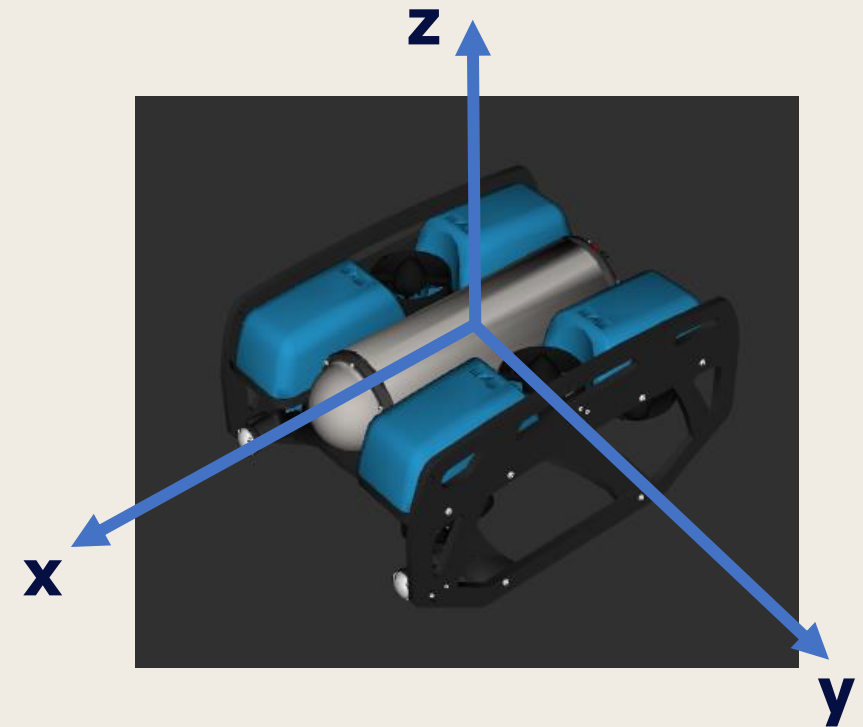
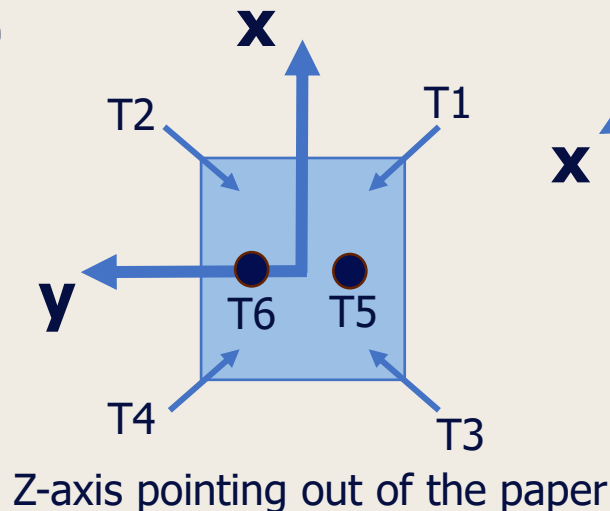
Marine Simulator Control (marsim_control) package

- Package where control-related source code will be placed
- Common scripts where common functions are placed
 - marsim_control/bluerov2_utils.py
 - marsim_control/marsim_utils.py
- Control scripts for BlueROV2
 - Two types of control commands
 - _control: a target position is given as command
 - _reqcontrol: a target change in position is given as command
 - Z position control:
 - scripts/bluerov2_pid_pose_z_control.py
 - scripts/bluerov2_pid_pose_z_reqcontrol.py
 - T1 to T4 are set to None
 - X, Y and Yaw control
 - scripts/bluerov2_pid_pose_xyyaw_reqcontrol.py
 - T5 and T6 are set to None
 - scripts/bluerov2_stop_thrusters.py

BlueROV2 thruster control configuration

- For thruster control, the BlueROV2 has:
- 12 State vector components:
 - Position (x, y, z)
 - Orientation (roll, pitch, yaw)
 - Linear velocity (v_x, v_y, v_z)
 - Angular velocity ($\omega_x, \omega_y, \omega_z$)
- 6 input vector components:
 - Commands for 6 thrusters

Positive thrust for T5 and T6 is pointing upwards, i.e., pushes the ROV downwards



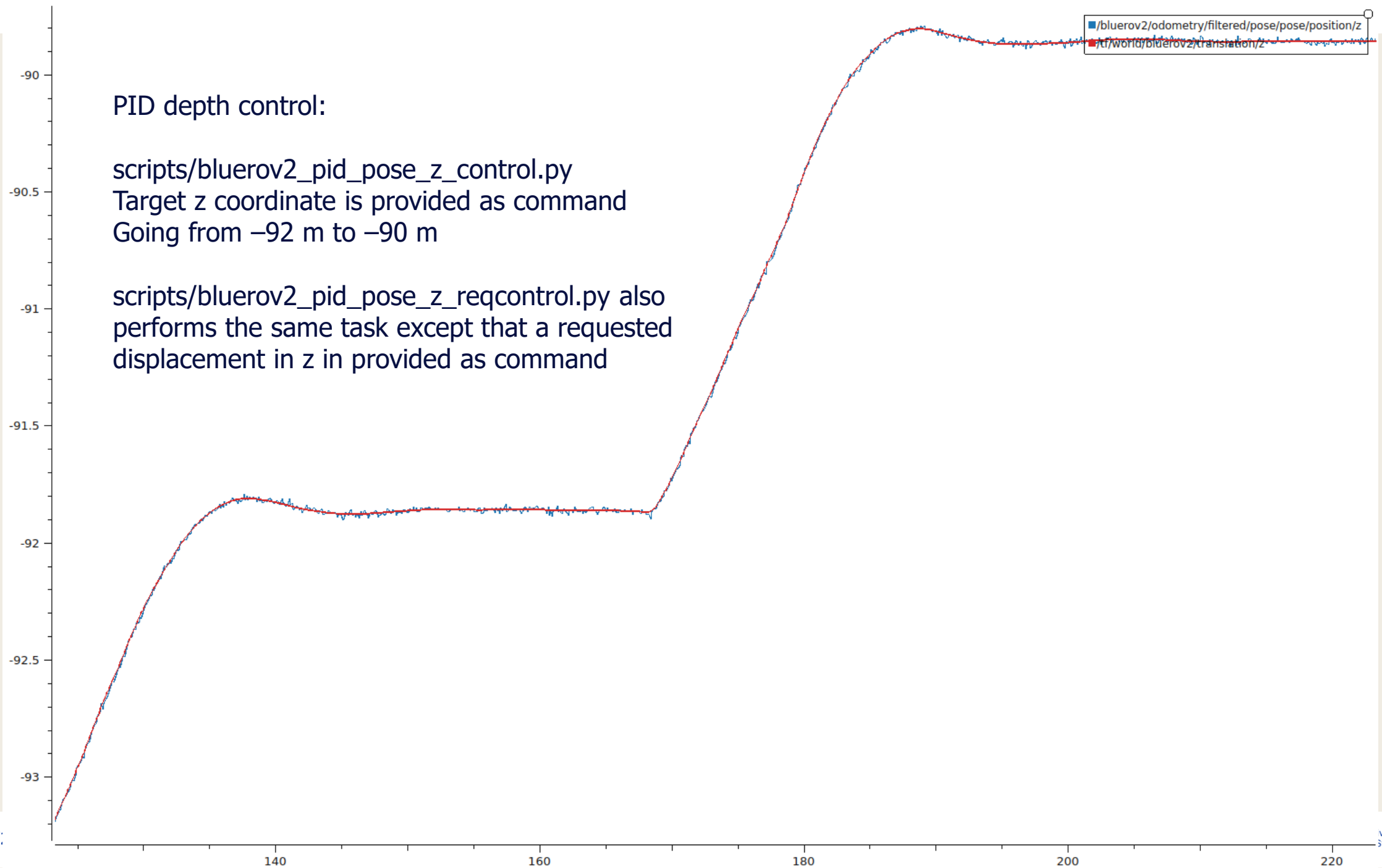
PID depth control:

`scripts/bluerov2_pid_pose_z_control.py`

Target z coordinate is provided as command

Going from -92 m to -90 m

`scripts/bluerov2_pid_pose_z_reqcontrol.py` also performs the same task except that a requested displacement in z is provided as command



PID x, y and yaw control:

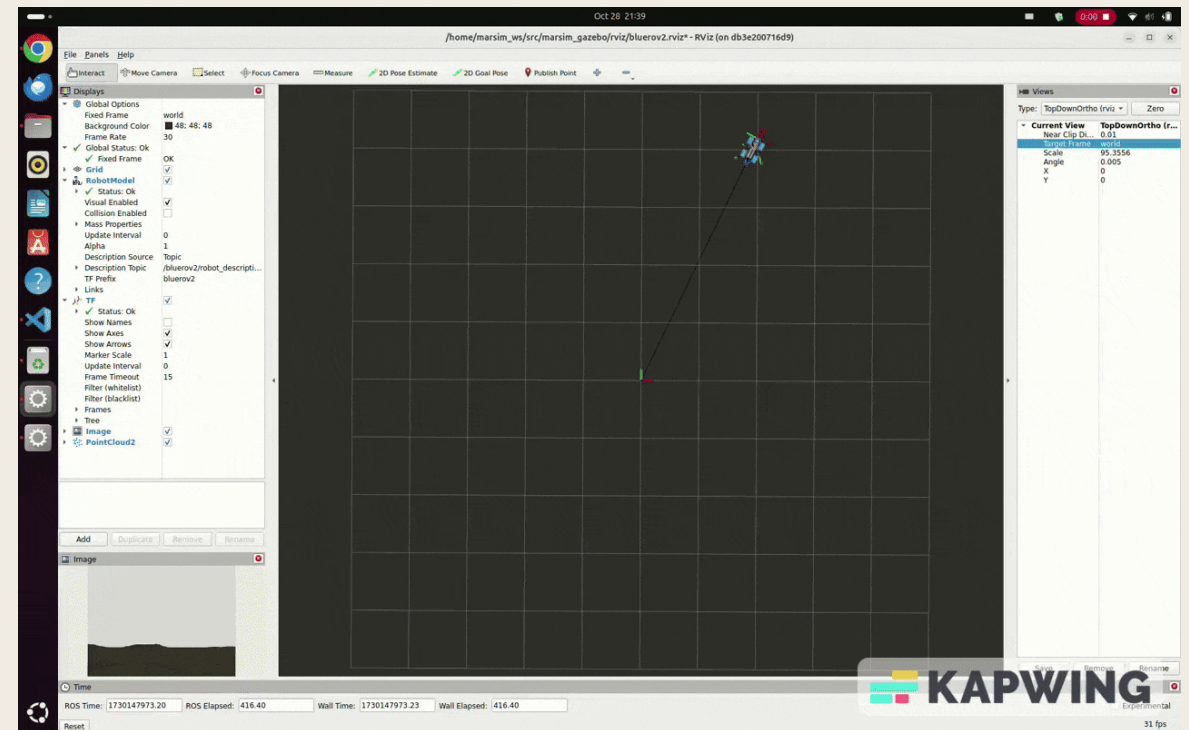
scripts/bluerov2_pid_pose_xyyaw_reqcontrol.py

Uses state machines

Rotate to required yaw heading

Move forward to request x and y

Rotate to final requested yaw heading



Planned updates for MARSIM v1.3

- Separate the documentation ppt into the different packages



Thank you for your attention!