default

January 31, 2023

0.1 Lab 0 26/01/2023

0.1.1 List 5 questions you have about ROS following the tutorial, answers you have found and things you still don't get

1. Is it possible to have a conflict for the listener, incase there are two nodes publishing topics to it at the same time? [multithreading?] I found a few links online, but I am not fully sure yet.
2. What will happen if the QoS setting for the publisher and the listener are different? Tried two different times, no change on the output. I thought it was related to duration, but on reading the docs realized that there is a lot more to the profile settings. Not sure what all of it means though.
3. How come we didn't use the `rcply.create_node()` fn? I think this is because we inherited the Node class so the node is getting created in our init fn
4. What if the same node is `rclpy.spin()` twice? As in if two nodes have the same properties? Learnt that each ROS node has to have a unique name. However, an ROS anonymous node is a workaround for this as it adds a unique ID to the name.
5. How this messaging system will extend to movement in robots? I guess I will find out.

0.1.2 Feedback on the bootcamp: What was easy and what was difficult to understand?

It was easy to follow through. The setup was easy. The analogy for nodes, topics and messages was helpful.