

University Rover Challenge

Complete Technical Documentation

& Startup Guide

University of Pittsburgh Robotics Club

ROS 2 Humble • NVIDIA Jetson Nano • Docker

Version 2.0 — January 2026

Platform: ROS 2 Humble Hawksbill
Hardware: NVIDIA Jetson Nano, Arduino
Deployment: Docker Containers
GUI: PyQt5

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Chapter 1

Project Overview

1.1 Introduction

This document provides comprehensive technical documentation for the University of Pittsburgh Robotics Club's University Rover Challenge (URC) rover system. The system integrates advanced robotics technologies including:

- **6-wheel differential drive system** with GoBilda motors
- **Multi-sensor fusion** including GPS, IMU, ultrasonic sensors, and cameras
- **ROS 2 Humble** for distributed robot communication
- **Docker containerization** for reproducible deployments
- **PyQt5 GUI system** for teleoperation and monitoring

1.2 Competition Tasks

The University Rover Challenge consists of multiple mission types:

Table 1.1: URC Competition Tasks

Task	Description
Autonomous Navigation	GPS-guided traversal of challenging Martian-analog terrain
Equipment Servicing	Precise manipulation tasks using robotic arm
Extreme Delivery	Package delivery in harsh environmental conditions
Science Operations	Sample collection and in-field analysis
Teleoperation	Manual control for complex scenarios

1.3 Key Specifications

Table 1.2: Rover System Specifications

Metric	Value
Navigation Accuracy	$\pm 2\text{m}$ GPS positioning
Video Latency	$< 200\text{ms}$ streaming
Control Response	$< 50\text{ms}$ command execution
Battery Life	4+ hours autonomous operation
Operating Range	1km+ radio communication
Motor Control	6 GoBilda motors (0–255 PWM)
Camera Frame Rate	30 Hz
IMU Update Rate	10 Hz
Serial Baud Rate	115200 bps

Chapter 2

System Architecture

2.1 High-Level Architecture

The rover system uses a **dual-container architecture** for optimal performance and separation of concerns.

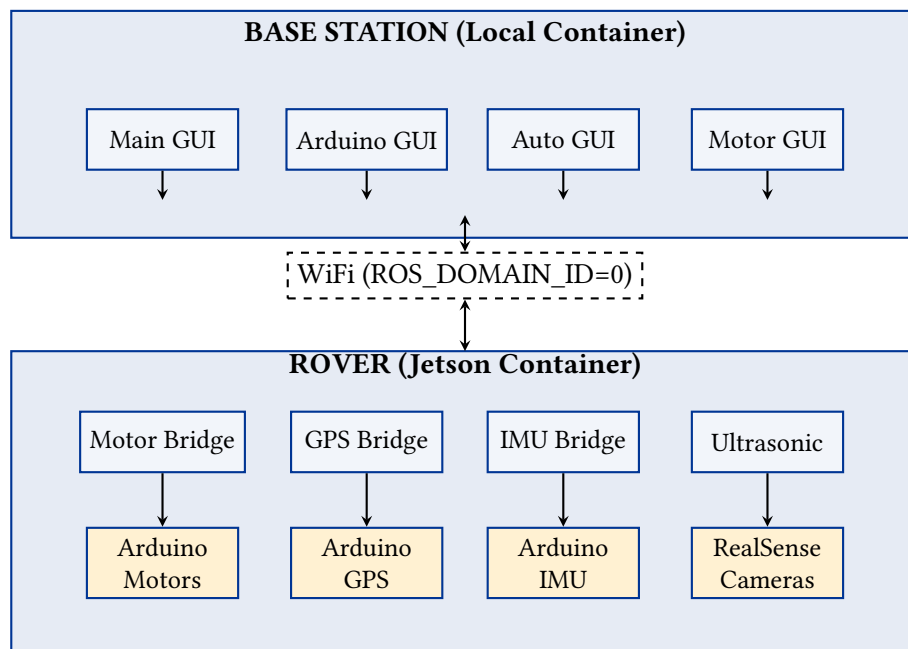


Figure 2.1: System Architecture Overview

2.2 Dual-Container Architecture

Table 2.1: Container Responsibilities

Container	Location	Purpose
Jetson Container	On-board rover	Hardware bridges, sensor acquisition, motor control, camera feeds
Local Container	Base station	GUI interfaces, visualization, high-level control, debugging

Tip

The dual-container architecture saves Jetson processing power for real-time control while enabling easier debugging with local GUI applications. ROS 2 communication works seamlessly over WiFi.

2.3 Communication Flow

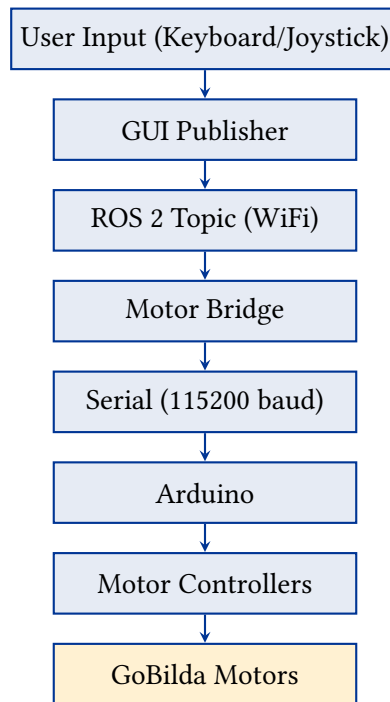


Figure 2.2: Motor Control Communication Flow

Chapter 3

Directory Structure

3.1 Project Layout

The project follows a modular organization:

```
1 URC/
2 |-- docker/                # Docker configuration
3 |   |-- jetson/            # On-board Jetson container
4 |   |   |-- Dockerfile
5 |   |   |-- docker-compose.yml
6 |   |   |-- start.sh
7 |   |   |-- supervisord.conf
8 |   |   +-- setup.py
9 |   |-- jetson_local/      # Alternative Jetson setup
10 |   +-- local/             # Base station container
11 |       |-- Dockerfile
12 |       |-- docker-compose.yml
13 |       |-- start_mac.sh
14 |       |-- start_linux.sh
15 |       +-- sim-launch.sh
16 |
17 |-- ros_bridge/           # ROS 2 hardware bridges
18 |   |-- arduino_bridge_base/ # Base class for bridges
19 |   |-- motor_bridge/       # Motor control system
20 |   |-- motor_subscriber/   # Legacy motor control
21 |   |-- gps_bridge/        # GPS sensor bridge
22 |   |-- imu_bridge/        # IMU sensor bridge
23 |   +-- ultrasonic_bridge/  # Ultrasonic sensor bridge
24 |
25 |-- guis/                 # PyQt5 GUI applications
26 |   |-- gen_gui.py          # Main control dashboard
27 |   |-- arduino_gui.py      # Hardware control interface
28 |   |-- auto_gui.py         # Autonomous navigation
29 |   |-- json_motorGUI.py    # Motor/Arm keyboard control
30 |   |-- publishers/         # ROS 2 publisher classes
31 |   |-- subscribers/        # ROS 2 subscriber classes
32 |   +-- camera/             # Camera utilities
33 |
34 |-- simulation/           # Gazebo simulation
35 |   +-- colcon_ws/         # ROS 2 workspace
36 |
37 |-- README.md
38 |-- CONTRIBUTING.md
39 +-- Makefile
```

Listing 3.1: Project Directory Structure

3.2 Key Directories

3.2.1 Docker Configuration

- `docker/jetson/` — On-board rover container with NVIDIA runtime support
- `docker/local/` — Base station container with X11 forwarding for GUI
- `docker/jetson_local/` — Alternative hybrid setup

3.2.2 ROS Bridge

- `arduino_bridge_base/` — Base class providing serial communication (248 lines)
- `motor_bridge/` — Unified motor control with multiple input sources
- `gps_bridge/` — NMEA sentence parsing and publishing
- `imu_bridge/` — BNO055 9-axis IMU integration
- `ultrasonic_bridge/` — Multi-sensor distance measurement

3.2.3 GUI System

- `gen_gui.py` — Main dashboard (623 lines) with camera feeds and sensor data
- `arduino_gui.py` — Joystick-style motor control (617 lines)
- `json_motorGUI.py` — Keyboard hotkey control (292 lines)
- `publishers/` — `MotorPublisher`, `TwistPublisher` classes
- `subscribers/` — `IMUSubscriber`, `GPSSubscriber`, data parsers

Chapter 4

Hardware Requirements

4.1 On-Board Computer

Table 4.1: Jetson Nano Specifications

Component	Specification
Computer	NVIDIA Jetson Nano (4GB)
Storage	64GB+ SD Card or NVMe SSD
Power	5V 4A barrel jack
Cooling	Active fan (recommended)

4.2 Motor System

Table 4.2: Motor System Specifications

Component	Specification
Motors	6x GoBilda motors
Motor Controllers	3x dual H-bridge controllers
Arduino	Arduino Mega 2560 (recommended)
PWM Range	0–255
Wheel Base	0.7384 meters
Max Speed	1.0 m/s

4.2.1 Pin Configuration

Table 4.3: Arduino Motor Pin Configuration

Motor	PWM Pin	Direction Pin	Side
Front Left	2	53	Left
Middle Left	4	51	Left
Back Left	6	49	Left
Front Right	3	52	Right
Middle Right	5	50	Right
Back Right	7	48	Right

4.3 Sensors

Table 4.4: Sensor Configuration

Sensor	Model	Connection	Rate
IMU	Adafruit BNO055 (9-axis)	Serial 115200	10 Hz
GPS	RTK GPS module	Serial 115200	1 Hz
Cameras	2x Intel RealSense D435	USB 3.0	30 Hz
Ultrasonic	3x HC-SR04	Arduino GPIO	10 Hz

4.3.1 Ultrasonic Sensor Pins

Table 4.5: Ultrasonic Sensor Pin Configuration

Sensor	Trigger Pin	Echo Pin
Sensor 1	8	9
Sensor 2	50	51
Sensor 3	48	49

4.4 Serial Port Configuration

Table 4.6: Serial Port Assignments

Device	Port	Baud Rate	Notes
Motors	/dev/ttyACM1	115200	Hardcoded in MotorBridge
GPS	/dev/ttyACM0	115200	Configurable
IMU	Auto-detect	115200	Tries multiple ports
Ultrasonic	Arduino internal	115200	No separate port

Chapter 5

Software Dependencies

5.1 System Requirements

- **Operating System:** Ubuntu 22.04 LTS
- **ROS Version:** ROS 2 Humble Hawksbill
- **Python:** 3.10+
- **Docker:** 20.10+

5.2 Python Dependencies

```
1 # Core ROS 2
2 rclpy
3 ros2cli
4
5 # Hardware Communication
6 pyserial>=3.5
7 pyrealsense2>=2.50.0
8
9 # GUI Framework
10 PyQt5>=5.15.0
11 PyQt5-sip
12
13 # Computer Vision
14 opencv-python>=4.5.0
15 numpy<2.0
16
17 # ROS 2 Message Bridges
18 cv_bridge
19 sensor_msgs
20 geometry_msgs
21 std_msgs
```

Listing 5.1: Python Package Requirements

5.3 System Packages (APT)

```
1 # Base development
2 python3-pip python3-pyqt5 python3-pyqt5.qtsvg
3
4 # Graphics libraries (for GUI)
```

```
5 libxcb-xinerama0 libxcb-cursor0 libxkbcommon-x11-0
6 libgl1-mesa-glx libgl1-mesa-dri mesa-utils x11-apps
7
8 # ROS 2 Humble
9 ros-humble-desktop ros-dev-tools
10 ros-humble-teleop-twist-keyboard ros-humble-joy
11
12 # Intel RealSense
13 librealsense2-utils librealsense2-dev
14 ros-humble-librealsense2-* ros-humble-realsense2-*
```

Listing 5.2: System Package Requirements

5.4 Arduino Libraries

- Adafruit_Sensor — Unified sensor abstraction layer
- Adafruit_BNO055 — 9-axis IMU driver library

Chapter 6

Docker Configuration

6.1 Jetson Container

6.1.1 Overview

The Jetson container runs on-board the rover and manages all hardware interfaces.

```
1 cd docker/jetson
2 sudo docker build -t urc_jetson .
3 sudo docker-compose up -d
```

Listing 6.1: Build and Start Jetson Container

6.1.2 Key Features

- NVIDIA GPU support (runtime: nvidia)
- Privileged mode for device access
- Host network mode for ROS 2 communication
- Supervisor process management

6.1.3 Device Mappings

```
1 devices:
2 - /dev:/dev                # All devices
3 - /dev/bus/usb:/dev/bus/usb # USB devices
4 - /dev/video0:/dev/video0  # Camera 1
5 - /dev/video1:/dev/video1  # Camera 2
```

Listing 6.2: Docker Compose Device Configuration

6.1.4 Environment Variables

```
1 environment:
2 - ROS_DOMAIN_ID=0
3 - ROS_LOCALHOST_ONLY=0
4 - NVIDIA_DRIVER_CAPABILITIES=all
5 - NVIDIA_VISIBLE_DEVICES=all
```

Listing 6.3: Jetson Environment Variables

6.1.5 Supervised Processes

Table 6.1: Supervisor Managed Processes

Process	Description	Auto-restart
setup	RealSense camera initialization	Yes
gps_bridge	GPS data publisher	Yes
motor_bridge	Motor command handler	Yes
ultrasonic_bridge	Ultrasonic sensor publisher	Yes

6.2 Local Container (Base Station)

6.2.1 macOS Setup

```

1 # Prerequisite: Install XQuartz and enable network clients
2 # System Preferences > Security > Allow connections
3
4 cd docker/local
5 chmod +x start_mac.sh
6 ./start_mac.sh

```

Listing 6.4: macOS Container Startup

6.2.2 Linux Setup

```

1 cd docker/local
2 chmod +x start_linux.sh
3 ./start_linux.sh

```

Listing 6.5: Linux Container Startup

6.2.3 Local Environment Variables

```

1 environment:
2   - ROS_DOMAIN_ID=0
3   - ROS_LOCALHOST_ONLY=0
4   - QT_X11_NO_MITSHM=1
5   - DISPLAY=${DISPLAY}

```

Listing 6.6: Local Container Environment

6.3 Simulation Container

```

1 cd docker/local
2 ./sim-launch.sh
3
4 # Launch simulation
5 ros2 launch my_robot_description display.launch.py use_sim_time:=true

```

Listing 6.7: Simulation Startup

Chapter 7

Quick Start Guide

7.1 Prerequisites

7.1.1 Install Docker

```
1 # Linux
2 curl -fsSL https://get.docker.com -o get-docker.sh
3 sudo sh get-docker.sh
4
5 # macOS
6 brew install --cask docker
```

Listing 7.1: Docker Installation

7.1.2 Clone Repository

```
1 git clone https://github.com/pitt-robotics/URC.git
2 cd URC
```

Listing 7.2: Clone Repository

7.1.3 Connect Hardware

1. Connect Arduino to USB port
2. Connect RealSense cameras to USB 3.0 ports
3. Power on motor controllers
4. Verify serial ports: `ls /dev/ttyACM*`

7.2 Option A: Full System Startup

Important

This option requires both the rover (Jetson) and base station (local machine) to be on the same WiFi network.

7.2.1 Step 1: Start Jetson Container (on rover)

```
1 cd docker/jetson
2 sudo ./start.sh
```

7.2.2 Step 2: Start Local Container (on base station)

```
1 # macOS
2 cd docker/local
3 ./start_mac.sh
4
5 # Linux
6 cd docker/local
7 ./start_linux.sh
```

7.2.3 Step 3: Launch GUI

```
1 # Inside local container
2 source /opt/ros/humble/local_setup.bash
3 cd /app
4 python3 -m guis.gen_gui
```

7.3 Option B: Simulation Only

```
1 cd docker/local
2 ./sim-launch.sh
3
4 # In another terminal (inside container)
5 ros2 launch my_robot_description display.launch.py use_sim_time:=true
```

7.4 Option C: Development Mode

```
1 # Start local container
2 cd docker/local
3 ./start_linux.sh
4
5 # Inside container
6 source /opt/ros/humble/local_setup.bash
7 cd /app
8
9 # Run individual components
10 python3 ros_bridge/motor_bridge/launch_motor_bridge.py
11 python3 -m guis.arduino_gui
```

Chapter 8

Detailed Startup Procedures

8.1 Jetson On-Board Startup

```
1 # 1. SSH into Jetson
2 ssh nvidia@<jetson-ip>
3
4 # 2. Navigate to project
5 cd /path/to/URC
6
7 # 3. Build and start container (first time)
8 cd docker/jetson
9 sudo docker build -t urc_jetson .
10 sudo docker-compose up -d
11
12 # 4. Verify container is running
13 sudo docker ps
14
15 # 5. Check supervised processes
16 sudo docker exec -it pitt_urc_jetson supervisorctl status
17
18 # Expected output:
19 # gps_bridge          RUNNING    pid 123, uptime 0:01:00
20 # motor_bridge        RUNNING    pid 124, uptime 0:01:00
21 # setup                RUNNING    pid 125, uptime 0:01:00
22 # ultrasonic_bridge    RUNNING    pid 126, uptime 0:01:00
23
24 # 6. View logs
25 sudo docker exec -it pitt_urc_jetson tail -f /app/motor_bridge.log
```

Listing 8.1: Complete Jetson Startup Procedure

8.2 Base Station Startup

8.2.1 macOS Procedure

```
1 # 1. Start XQuartz
2 open -a XQuartz
3
4 # 2. Enable network clients (if not done)
5 # XQuartz > Preferences > Security > Allow connections
6
7 # 3. Navigate to project
8 cd /path/to/URC/docker/local
9
```

```
10 # 4. Start container
11 ./start_mac.sh
12
13 # 5. Source ROS 2
14 source /opt/ros/humble/local_setup.bash
15
16 # 6. Launch main GUI
17 cd /app
18 python3 -m guis.gen_gui
```

Listing 8.2: macOS Base Station Startup

8.2.2 Linux Procedure

```
1 # 1. Navigate to project
2 cd /path/to/URC/docker/local
3
4 # 2. Start container
5 ./start_linux.sh
6
7 # 3. Source ROS 2
8 source /opt/ros/humble/local_setup.bash
9
10 # 4. Launch main GUI
11 cd /app
12 python3 -m guis.gen_gui
```

Listing 8.3: Linux Base Station Startup

8.3 Verification Steps

8.3.1 Check ROS 2 Connectivity

```
1 # List all active nodes
2 ros2 node list
3
4 # Expected:
5 # /motor_bridge
6 # /gps_bridge
7 # /imu_bridge
8 # /ultrasonic_bridge
9
10 # List all topics
11 ros2 topic list
12
13 # Expected:
14 # /cmd_vel
15 # /motor_control_input
16 # /drive_data
17 # /gps_data
18 # /imu_data
19 # /ultrasonic_data
20 # /camera/gray/image_raw
21 # /camera/depth/image_raw
```

Listing 8.4: ROS 2 Verification Commands

8.3.2 Test Motor Commands

Warning

Be careful when testing motor commands! Ensure the rover is in a safe position before sending movement commands.

```
1 # Send stop command
2 ros2 topic pub --once /motor_control_input std_msgs/String \
3   "data: '0,0,0,0,0,0'"
4
5 # Send forward command (be careful!)
6 ros2 topic pub --once /motor_control_input std_msgs/String \
7   "data: '100,0,0,0,0,0'"
```

Listing 8.5: Motor Command Testing

8.3.3 Monitor Sensor Data

```
1 # IMU data
2 ros2 topic echo /imu_data
3
4 # GPS data
5 ros2 topic echo /gps_data
6
7 # Ultrasonic data
8 ros2 topic echo /ultrasonic_data
```

Listing 8.6: Sensor Data Monitoring

Chapter 9

ROS 2 Architecture

9.1 Node Overview

Table 9.1: ROS 2 Nodes

Node	Package	Purpose
motor_bridge	ros_bridge	Motor command handling and feed-back
gps_bridge	ros_bridge	GPS NMEA data publishing
imu_bridge	ros_bridge	IMU orientation data publishing
ultrasonic_bridge	ros_bridge	Distance measurement publishing
gray_and_depth_publisher	guis.camera	Camera feed publishing

9.2 Topic Architecture

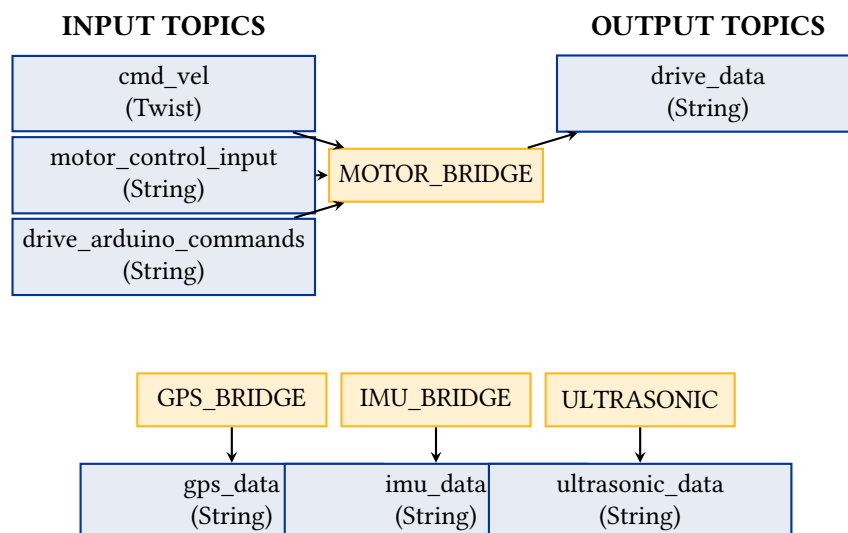


Figure 9.1: ROS 2 Topic Architecture

9.3 Message Formats

9.3.1 Motor Control Input (String)

```
1 Format: "linear_x,linear_y,linear_z,angular_x,angular_y,angular_z"
2 Example: "100,0,0,0,0,50" # Forward with slight right turn
```

Listing 9.1: Motor Command Format

9.3.2 IMU Data (String)

```
1 Format: "X: <value>\tY: <value>\tZ: <value>"
2 Example: "X: 0.123\tY: 0.456\tZ: 0.789"
```

Listing 9.2: IMU Data Format

9.3.3 GPS Data (String)

```
1 NMEA sentences:
2 $GNGLL,4024.12345,N,07952.12345,W,123456.00,A,A*6B
3 $GAGSV,3,1,12,01,45,123,38,02,67,234,42,...
```

Listing 9.3: GPS NMEA Format

9.3.4 Ultrasonic Data (String)

```
1 Format: "distance1_cm, distance2_cm, distance3_cm, "
2 Example: "45, 120, 88, "
```

Listing 9.4: Ultrasonic Data Format

9.4 Bridge Class Hierarchy

```
1 ArduinoBridgeBase(Node)           # Base class (248 lines)
2   |-- MotorBridge                  # Motor control
3   |-- GPSBridge                    # GPS data
4   |-- IMUBridge                    # IMU data
5   +-- UltrasonicBridge              # Ultrasonic data
```

Listing 9.5: Bridge Class Structure

Base Class Features:

- Serial port initialization (115200 baud)
- Generic ROS 2 topic subscription/publishing
- Timer-based Arduino reading (100ms default)
- Error handling and logging
- Automatic reconnection attempts

Chapter 10

Hardware Interfaces

10.1 Motor Control

10.1.1 Arduino Firmware

Location: ros_bridge/motor_subscriber/motor_serial/motor_serial.ino

```
1 // Simplified differential drive
2 left_speed = linear_x - angular_z;
3 right_speed = linear_x + angular_z;
4
5 // PWM mapping
6 pwm_left = map(left_speed, -100, 100, -255, 255);
7 pwm_right = map(right_speed, -100, 100, -255, 255);
8
9 // Direction Control
10 // HIGH = Forward
11 // LOW = Reverse
```

Listing 10.1: Motor Control Logic

10.2 IMU (BNO055)

Location: ros_bridge/imu_bridge/imu_serial/imu_serial.ino

```
1 Adafruit_BNO055 bno = Adafruit_BNO055(55);
2 bno.setExtCrystalUse(true); // External crystal for accuracy
3
4 // Output Format
5 Serial.print("X: "); Serial.print(event.orientation.x);
6 Serial.print("\tY: "); Serial.print(event.orientation.y);
7 Serial.print("\tZ: "); Serial.println(event.orientation.z);
```

Listing 10.2: IMU Configuration

10.2.1 Data Processing

```
1 # IMUDataParser.py
2 import math
3
4 distance = math.sqrt(
5     (x_cur - x_prev)**2 +
6     (y_cur - y_prev)**2 +
7     (z_cur - z_prev)**2
```



```

8 )
9 velocity = distance / time_delta
10 vertical_tilt = math.degrees(math.atan2(y_delta, z_delta))
11 horizontal_tilt = math.degrees(math.atan2(y_delta, x_delta))

```

Listing 10.3: IMU Data Parser

10.3 GPS

Location: `ros_bridge/gps_bridge/gps/gps.ino`

Table 10.1: NMEA Sentence Types

Type	Purpose
GNGLL	Geographic position (latitude/longitude)
GAGSV	GPS satellites in view + SNR
GBGSV	BeiDou satellites in view + SNR

10.4 Ultrasonic Sensors

Location: `ros_bridge/ultrasonic_bridge/multiple_untrasonic_sensors/`

```

1 duration = pulseIn(echoPin, HIGH);
2 distance_cm = (duration / 2) / 29.1;

```

Listing 10.4: Ultrasonic Distance Calculation

10.5 RealSense Cameras

Location: `guis/camera/camera_cv_test.py`

```

1 import pyrealsense2 as rs
2
3 # Color stream
4 config.enable_stream(rs.stream.color, 640, 480, rs.format.bgr8, 30)
5
6 # Depth stream
7 config.enable_stream(rs.stream.depth, 640, 480, rs.format.z16, 30)

```

Listing 10.5: RealSense Configuration

Chapter 11

GUI System

11.1 Main Control GUI

File: guis/gen_gui.py (623 lines)

Table 11.1: Main GUI Components

Section	Function
Title Bar	Connection status (ONLINE/OFFLINE)
Navigation Tabs	Switch between competition modes
Camera Feeds	3 video displays (primary, secondary, auxiliary)
IMU Display	Speed, vertical tilt, horizontal tilt
System Controls	Toggle IMU, GPS, orientation
Emergency Stop	Red button for immediate halt

```
1 python3 -m guis.gen_gui
```

Listing 11.1: Launch Main GUI

11.2 Motor/Arm GUI Hotkeys

File: guis/json_motorGUI.py (292 lines)

Table 11.2: Motor Control Hotkeys

Key	Action
I	Forward
, (comma)	Backward
L	Turn Right
J	Turn Left
Q	Speed Up
Z	Slow Down
K	Stop

Table 11.3: Arm Control Hotkeys

Key	Action
0/9	Claw open/close
M/N	Base shift right/left
U/J	Bottom joint forward/backward
I/K	Middle joint forward/backward
O/L	Top joint forward/backward
Y/H	Wrist clockwise/counterclockwise
Escape	Emergency stop all

11.3 Publisher Classes

Location: `guis/publishers/publisher.py`

```

1 class MotorPublisher(GenericPublisher):
2     def __init__(self):
3         super().__init__('motor_control_input', String)
4
5     def publish_motor_command(self, motor_values):
6         # motor_values: list of 6 floats
7         msg = String()
8         msg.data = ','.join(map(str, motor_values))
9         self.publisher.publish(msg)
10
11     def stop_all_motors(self):
12         self.publish_motor_command([0, 0, 0, 0, 0, 0])

```

Listing 11.2: MotorPublisher Class

```

1 class TwistPublisher(GenericPublisher):
2     def __init__(self):
3         super().__init__('cmd_vel', Twist)
4
5     def move_forward(self, speed):
6         msg = Twist()
7         msg.linear.x = float(speed)
8         self.publisher.publish(msg)
9
10    def turn_left(self, angular_speed):
11        msg = Twist()
12        msg.angular.z = float(angular_speed)
13        self.publisher.publish(msg)

```

Listing 11.3: TwistPublisher Class

Chapter 12

Development Workflow

12.1 Git Workflow

12.1.1 Branch Strategy

- main — Protected, requires PR review
- feature/* — New features
- bugfix/* — Bug fixes
- hotfix/* — Urgent production fixes

12.1.2 Standard Workflow

```
1 # 1. Fetch latest
2 git fetch origin
3
4 # 2. Create feature branch
5 git checkout -b feature/my-feature main
6
7 # 3. Make changes
8 # ... edit files ...
9
10 # 4. Stage and commit
11 git add .
12 git commit -m "feat: add my feature description"
13
14 # 5. Push to remote
15 git push origin feature/my-feature
16
17 # 6. Create Pull Request on GitHub
```

Listing 12.1: Git Development Workflow

12.1.3 Commit Message Format

```
1 type: description
2
3 Types:
4 - feat: New feature
5 - fix: Bug fix
6 - docs: Documentation
7 - refactor: Code refactoring
```

```
8 - test: Testing
9 - chore: Maintenance
```

Listing 12.2: Commit Message Types

12.2 Adding a New Sensor Bridge

12.2.1 Step 1: Create Arduino Firmware

```
1 // ros_bridge/new_sensor_bridge/new_sensor_serial/new_sensor_serial.ino
2 void setup() {
3     Serial.begin(115200);
4 }
5
6 void loop() {
7     // Read sensor
8     float value = readSensor();
9
10    // Send data
11    Serial.println(value);
12    delay(100);
13 }
```

Listing 12.3: New Sensor Arduino Code

12.2.2 Step 2: Create Python Bridge

```
1 # ros_bridge/new_sensor_bridge/new_sensor_bridge.py
2 from ros_bridge.arduino_bridge_base.arduino_bridge_base import ArduinoBridgeBase
3 from std_msgs.msg import String
4
5 class NewSensorBridge(ArduinoBridgeBase):
6     def __init__(self):
7         super().__init__(
8             node_name='new_sensor_bridge',
9             topic_name='new_sensor_data',
10            msg_type=String,
11            serial_port='/dev/ttyACM0',
12            baud_rate=115200
13        )
```

Listing 12.4: New Sensor Python Bridge

12.2.3 Step 3: Add to Supervisor

```
1 # docker/jetson/supervisord.conf
2 [program:new_sensor_bridge]
3 command=python3 /app/ros_bridge/new_sensor_bridge/new_sensor_bridge.py
4 stdout_logfile=/app/new_sensor_bridge.log
5 stderr_logfile=/app/new_sensor_bridge_err.log
6 autorestart=true
```

Listing 12.5: Supervisor Configuration Entry

Chapter 13

Troubleshooting

13.1 Common Issues

Issue	Cause	Solution
Serial port not found	Device not connected	Check USB connections, verify /dev/ttyACM* exists
Motors not responding	Wrong port or baud rate	Verify /dev/ttyACM1, check 115200 baud
ROS topics not visible	Domain ID mismatch	Ensure ROS_DOMAIN_ID=0 on both systems
GUI won't display	X11 forwarding issue	Check DISPLAY variable, restart XQuartz
Camera black screen	USB bandwidth	Use USB 3.0 ports, reduce resolution
High latency	Network congestion	Check WiFi signal, reduce message frequency

Table 13.1: Common Issues and Solutions

13.2 Serial Port Debugging

```

1 # List all serial ports
2 ls -la /dev/ttyACM* /dev/ttyUSB*
3
4 # Check port permissions
5 sudo chmod 666 /dev/ttyACM0
6
7 # Test serial communication
8 screen /dev/ttyACM0 115200
9
10 # Kill screen session: Ctrl+A, then K

```

Listing 13.1: Serial Port Debugging Commands

13.3 ROS 2 Debugging

```

1 # Check ROS environment
2 echo $ROS_DOMAIN_ID
3 echo $ROS_LOCALHOST_ONLY
4
5 # Source ROS 2
6 source /opt/ros/humble/local_setup.bash
7
8 # Verify discovery
9 ros2 daemon status
10 ros2 daemon start
11
12 # Check multicast
13 ros2 multicast receive

```

Listing 13.2: ROS 2 Debugging Commands

13.4 Docker Debugging

```

1 # Check container status
2 docker ps -a
3
4 # View container logs
5 docker logs pitt_urc_jetson
6
7 # Enter running container
8 docker exec -it pitt_urc_jetson bash
9
10 # Check supervisor status (inside Jetson container)
11 supervisorctl status
12 supervisorctl restart motor_bridge

```

Listing 13.3: Docker Debugging Commands

13.5 Log File Locations

Table 13.2: Log File Locations

Log	Location	Content
Motor Bridge	/app/motor_bridge.log	Motor commands, errors
GPS Bridge	/app/gps_bridge.log	NMEA sentences
Ultrasonic	/app/ultrasonic_bridge.log	Distance readings
Setup	/app/setup.log	Camera initialization

Chapter 14

API Reference

14.1 ArduinoBridgeBase

```
1 class ArduinoBridgeBase(Node):
2     """Base class for all Arduino serial bridges."""
3
4     def __init__(self, node_name, topic_name, msg_type,
5                 serial_port='/dev/ttyACM0', baud_rate=115200):
6         """
7         Initialize the bridge.
8
9         Args:
10             node_name: ROS 2 node name
11             topic_name: Topic to publish/subscribe
12             msg_type: ROS 2 message type (e.g., String)
13             serial_port: Serial port path
14             baud_rate: Baud rate (default: 115200)
15         """
16
17     def read_from_arduino(self):
18         """Read data from Arduino and publish to ROS topic."""
19
20     def write_to_arduino(self, data):
21         """Write data to Arduino serial port."""
```

Listing 14.1: ArduinoBridgeBase API

14.2 MotorPublisher

```
1 class MotorPublisher(GenericPublisher):
2     """Publisher for motor control commands."""
3
4     def publish_motor_command(self, motor_values: List[float]):
5         """
6         Publish motor command.
7
8         Args:
9             motor_values: List of 6 float values
10                          [linear_x, linear_y, linear_z,
11                           angular_x, angular_y, angular_z]
12         """
13
14     def set_motor_value(self, index: int, value: float):
15         """Set a specific motor value (0-5)."""
```



```
16
17 def set_all_motors(self, value: float):
18     """Set all motors to the same value."""
19
20 def stop_all_motors(self):
21     """Emergency stop - set all motors to 0."""
```

Listing 14.2: MotorPublisher API

14.3 TwistPublisher

```
1 class TwistPublisher(GenericPublisher):
2     """Publisher for geometry_msgs/Twist messages."""
3
4     def publish_twist(self, linear_x=0, linear_y=0, linear_z=0,
5                       angular_x=0, angular_y=0, angular_z=0):
6         """Publish a full Twist message."""
7
8     def move_forward(self, speed: float):
9         """Move forward at specified speed."""
10
11     def move_backward(self, speed: float):
12         """Move backward at specified speed."""
13
14     def turn_left(self, angular_speed: float):
15         """Turn left at specified angular speed."""
16
17     def turn_right(self, angular_speed: float):
18         """Turn right at specified angular speed."""
19
20     def stop(self):
21         """Stop all motion."""
```

Listing 14.3: TwistPublisher API

Appendix A

Environment Variables

Table A.1: Environment Variable Reference

Variable	Default	Description
ROS_DOMAIN_ID	0	ROS 2 domain for multi-device networking
ROS_LOCALHOST_ONLY	0	Allow network communication (0=yes, 1=no)
DISPLAY	:0	X11 display for GUI
QT_X11_NO_MITSHM	1	Qt X11 compatibility
NVIDIA_VISIBLE_DEVICES	all	GPU access (Jetson)
NVIDIA_DRIVER_CAPABILITIES	all	GPU capabilities (Jetson)

Appendix B

Quick Command Reference

```
1 # Docker
2 docker build -t urc_jetson .
3 docker-compose up -d
4 docker exec -it pitt_urc_jetson bash
5 docker logs pitt_urc_jetson
6
7 # ROS 2
8 source /opt/ros/humble/local_setup.bash
9 ros2 node list
10 ros2 topic list
11 ros2 topic echo /topic_name
12 ros2 topic pub --once /topic std_msgs/String "data: 'test'"
13
14 # GUI
15 python3 -m guis.gen_gui
16 python3 -m guis.arduino_gui
17 python3 -m guis.json_motorGUI
18
19 # Supervisor (inside Jetson container)
20 supervisorctl status
21 supervisorctl restart motor_bridge
22 supervisorctl tail -f motor_bridge
23
24 # Serial
25 ls /dev/ttyACM*
26 screen /dev/ttyACM0 115200
```

Listing B.1: Quick Command Reference

Appendix C

Network Ports

Table C.1: Network Port Reference

Port	Protocol	Service
7400	UDP	ROS 2 DDS Discovery
8000	HTTP	Motor/Arm GUI server
11311	TCP	ROS Master (legacy)

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For questions or contributions, please refer to `CONTRIBUTING.md` or open an issue on GitHub.