ROS-Industrial Basic Developer's Training Class

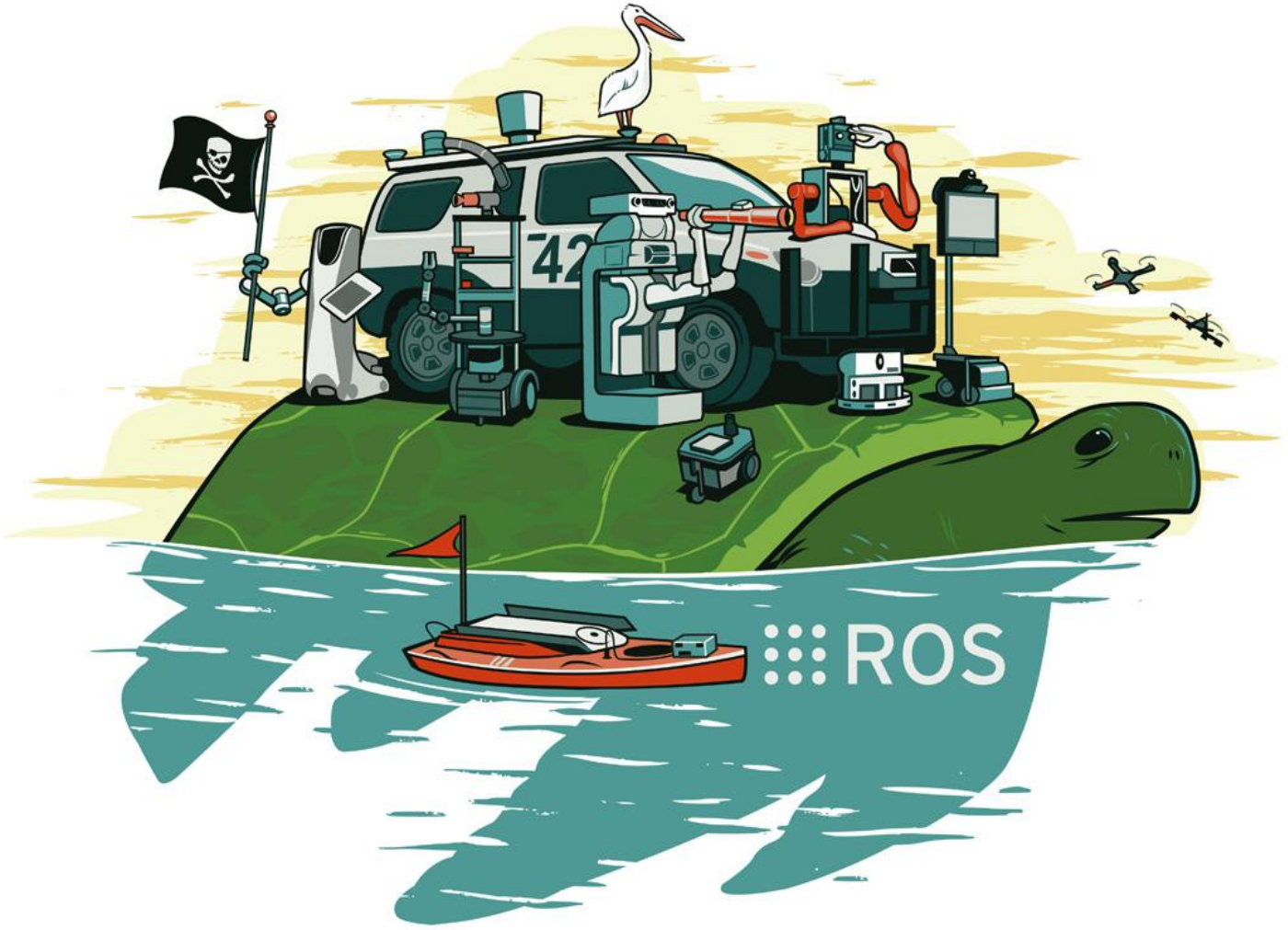
April 2015

Southwest Research Institute

Outline

- Intro to ROS
- Installing
- Packages / Nodes
- Parameters
- Messages / Topics

An Introduction to ROS



(Image taken from Willow Garage's "What is ROS?" presentation)

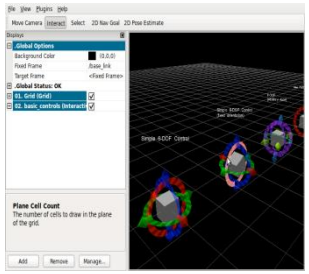
What is ROS?

ROS is…

=

Plumbing

+



Tools

+

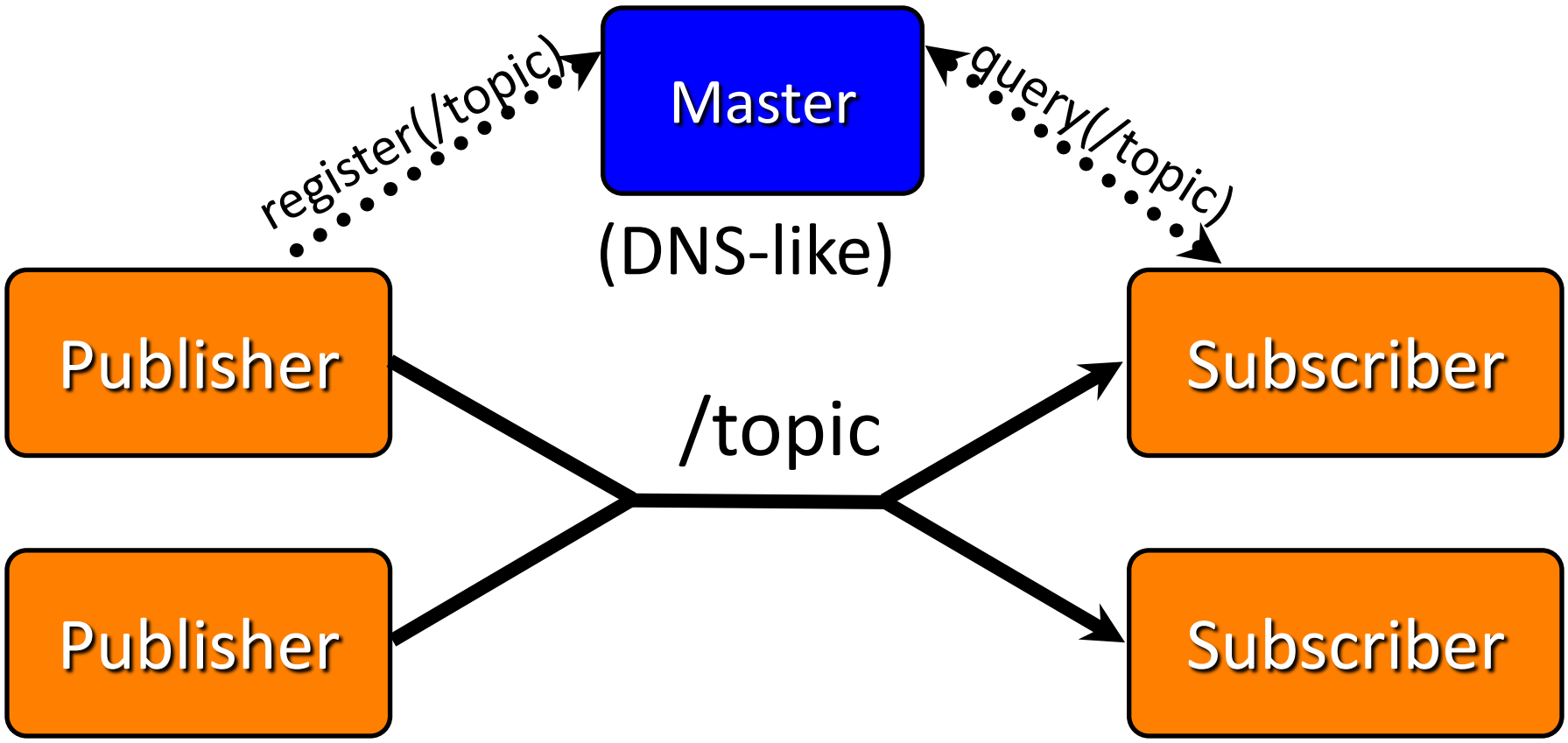
Capabilities

+

Ecosystem

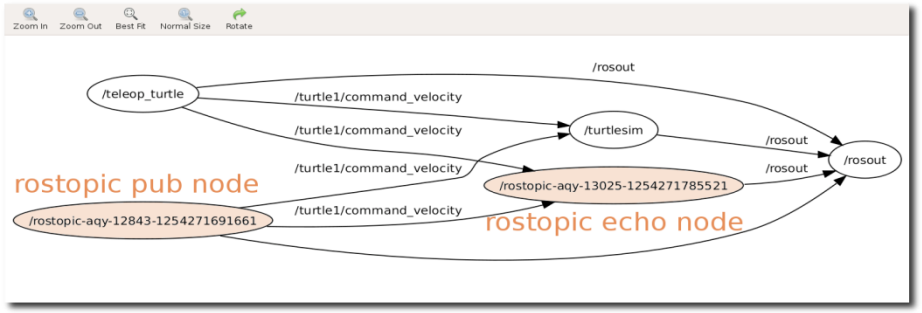
(Adapted from Willow Garage's "What is ROS?" Presentation)

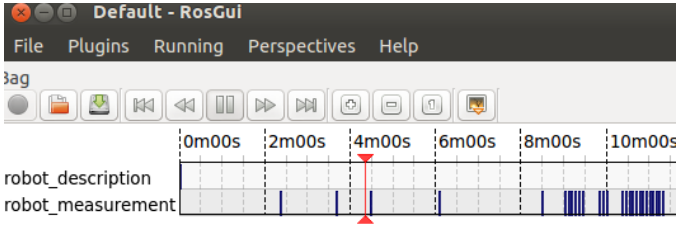
ROS is… plumbing

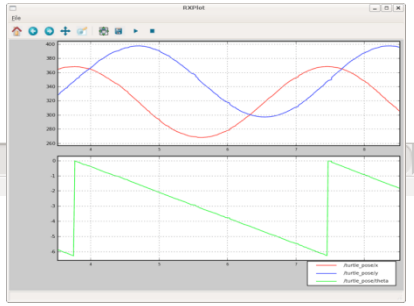


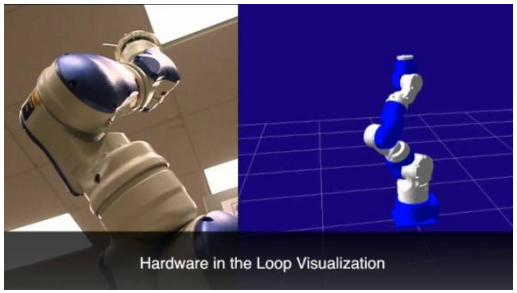
(Adapted from Willow Garage's "What is ROS?" Presentation)

ROS is …Tools

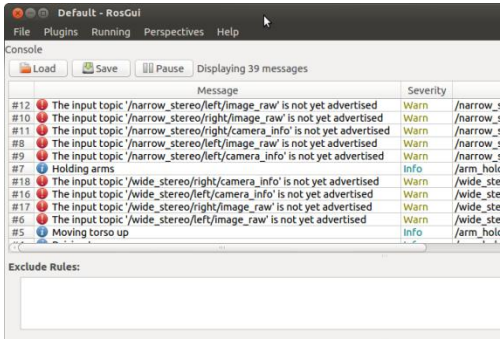






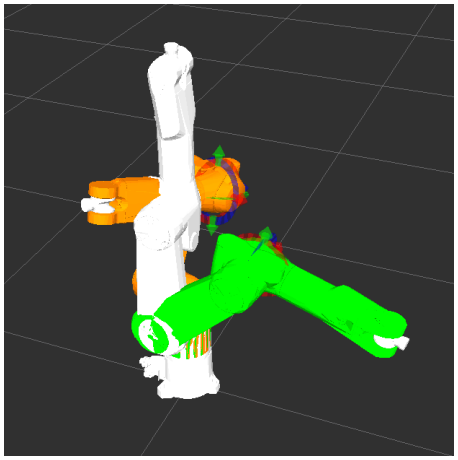


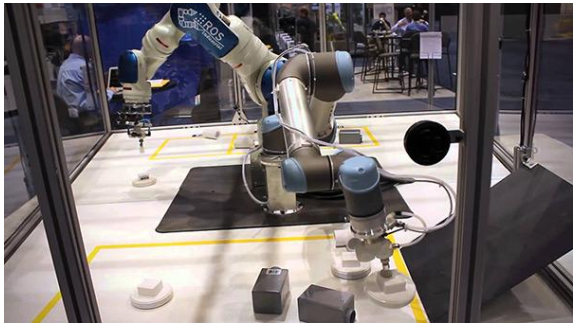
- logging/plotting
- graph visualization
- diagnostics
- visualization

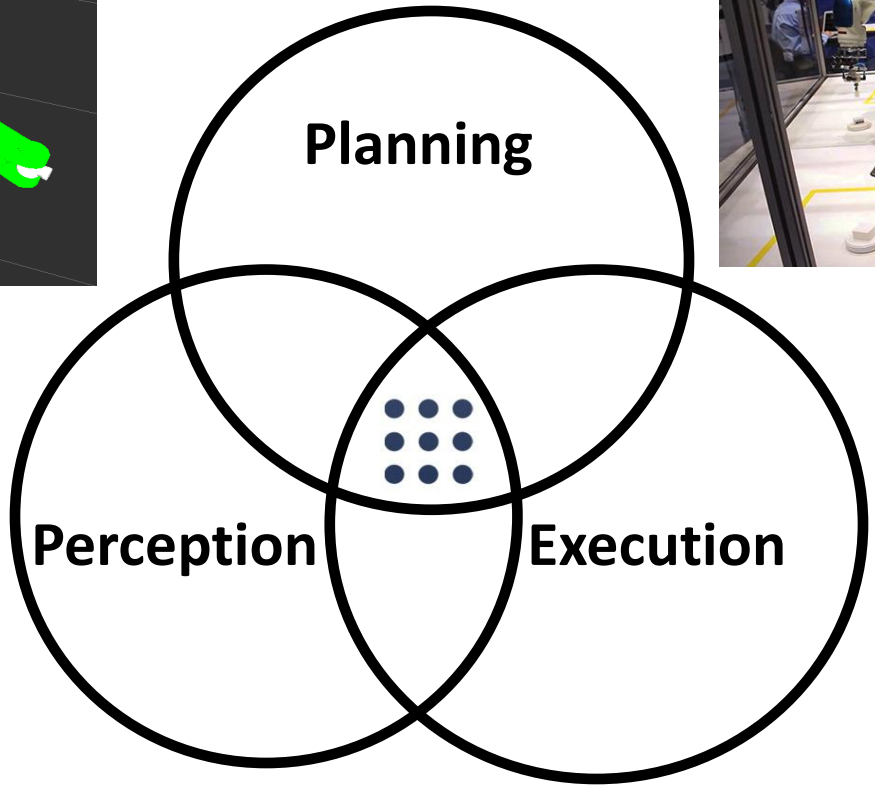


(Adapted from Willow Garage's "What is ROS?" Presentation)

ROS is…Capabilities







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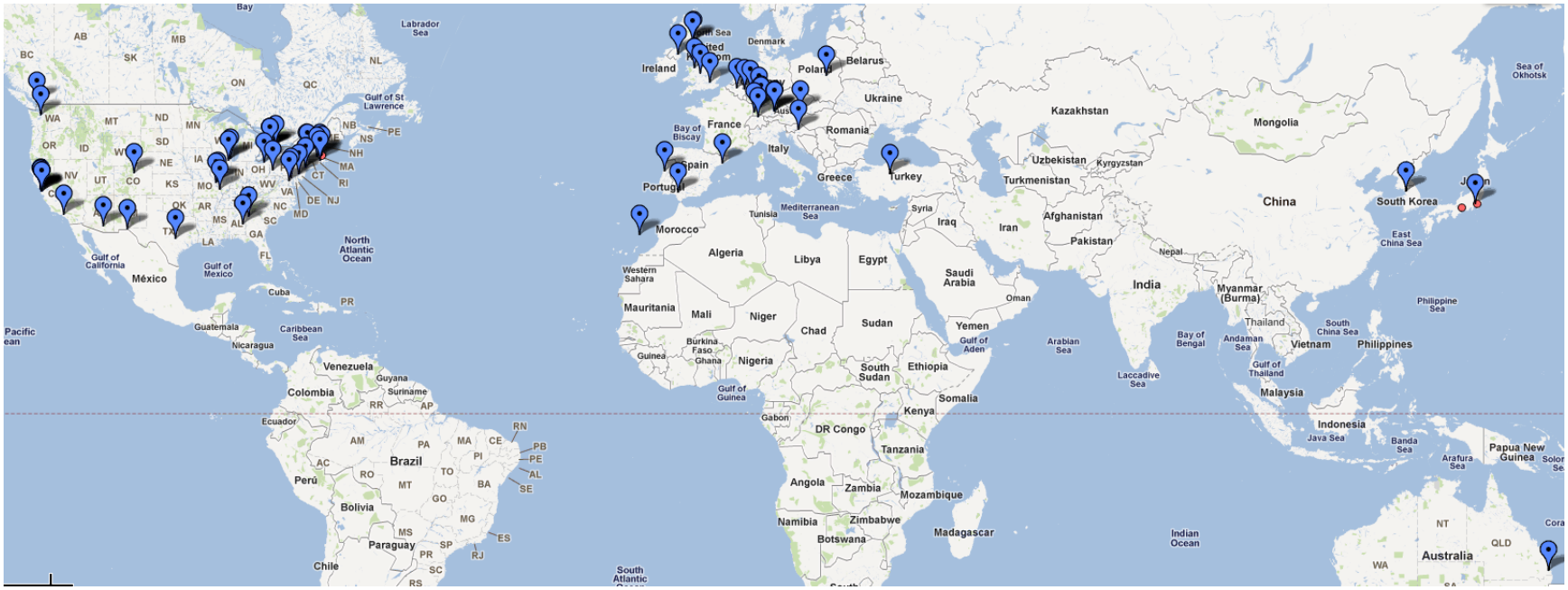
ROS is… an Ecosystem



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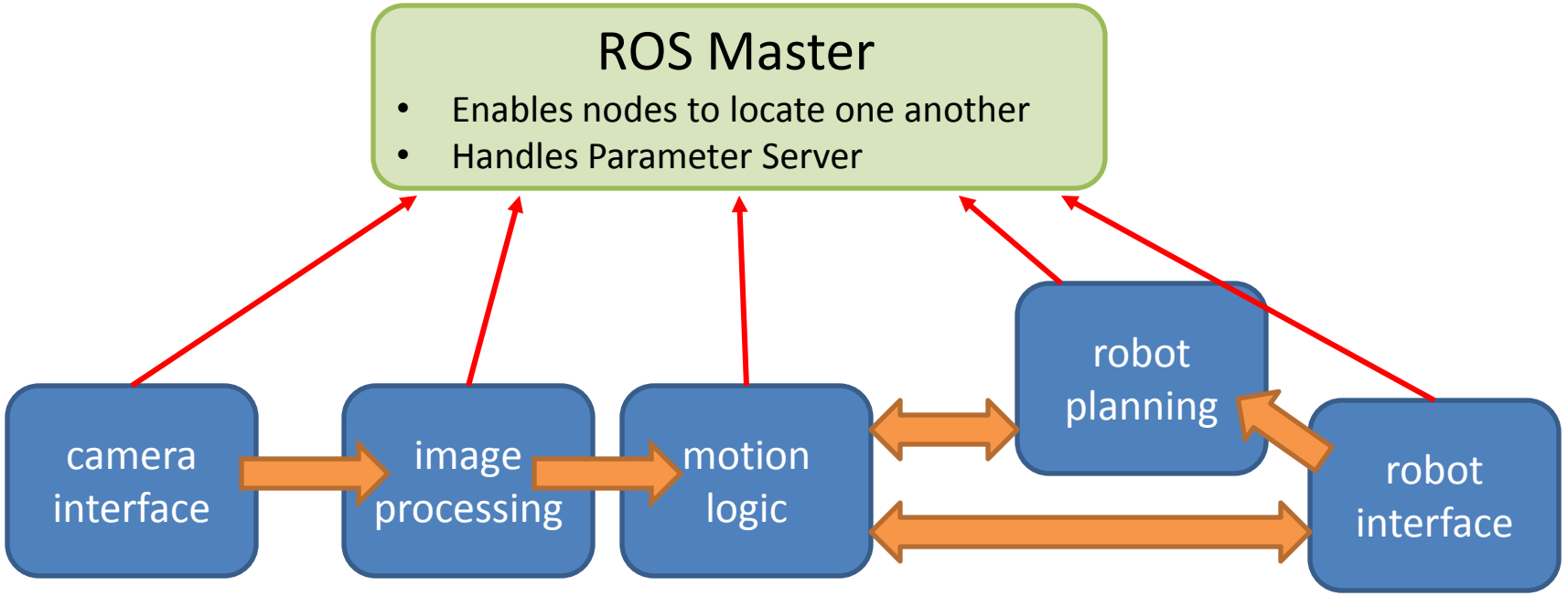
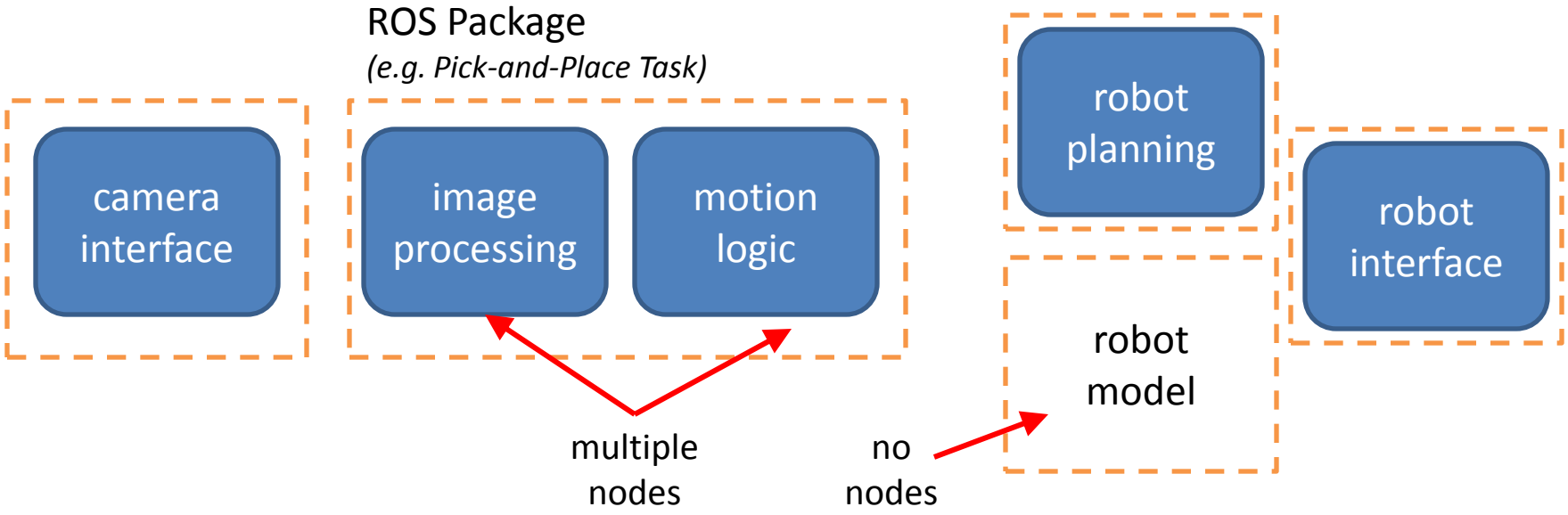
ROS Architecture: Nodes



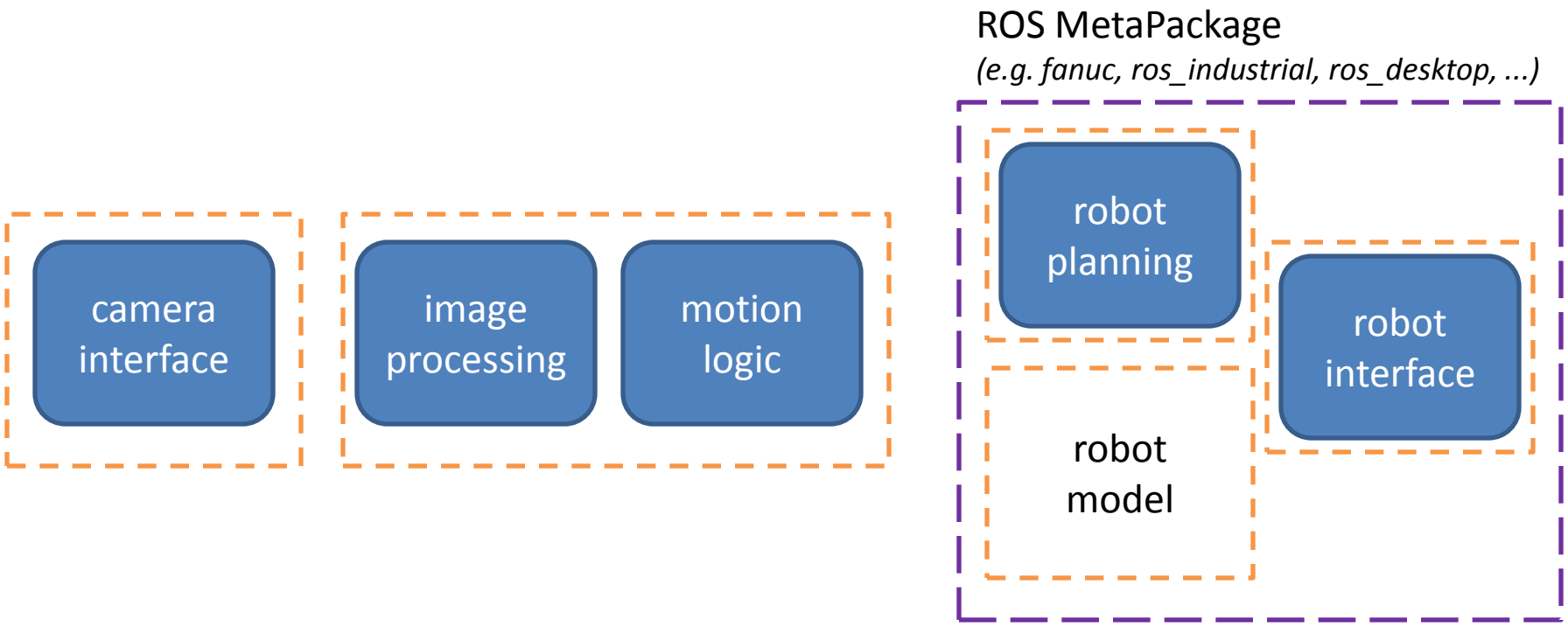
- A **Node** is a single ROS-enabled program
  - Most communication happens **between** nodes
  - Nodes can run on many different **devices**
- One **Master** per system

ROS Architecture: Packages



- ROS **Packages** are groups of related nodes/data
  - Many ROS commands are **package-oriented**

ROS Architecture: MetaPkg



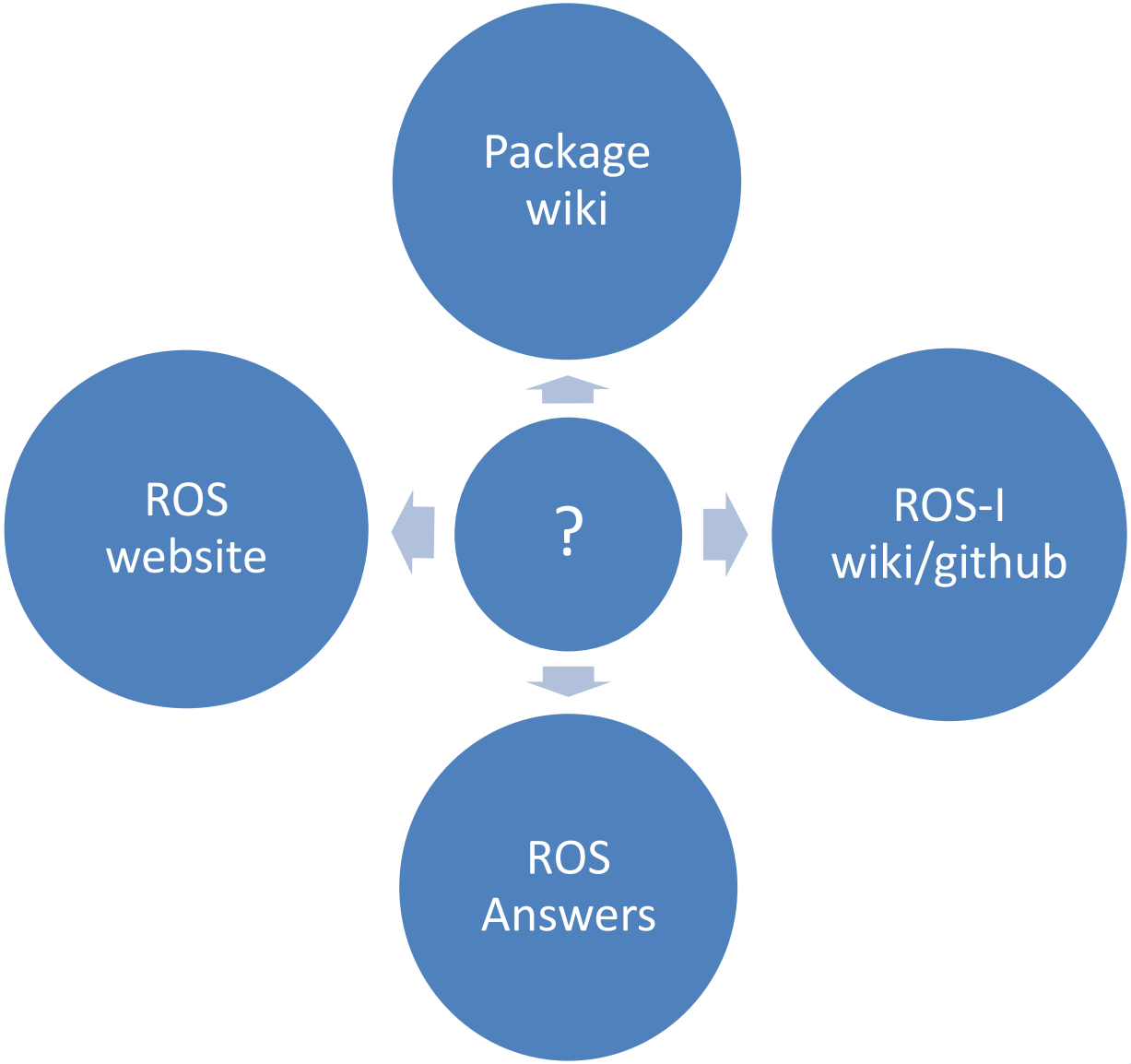
- **MetaPackages** are groups of related packages
  - Mostly for convenient install/deployment

ROS Programming

- ROS uses **platform-agnostic** methods for most communication
  - TCP/IP Sockets, XML, etc.

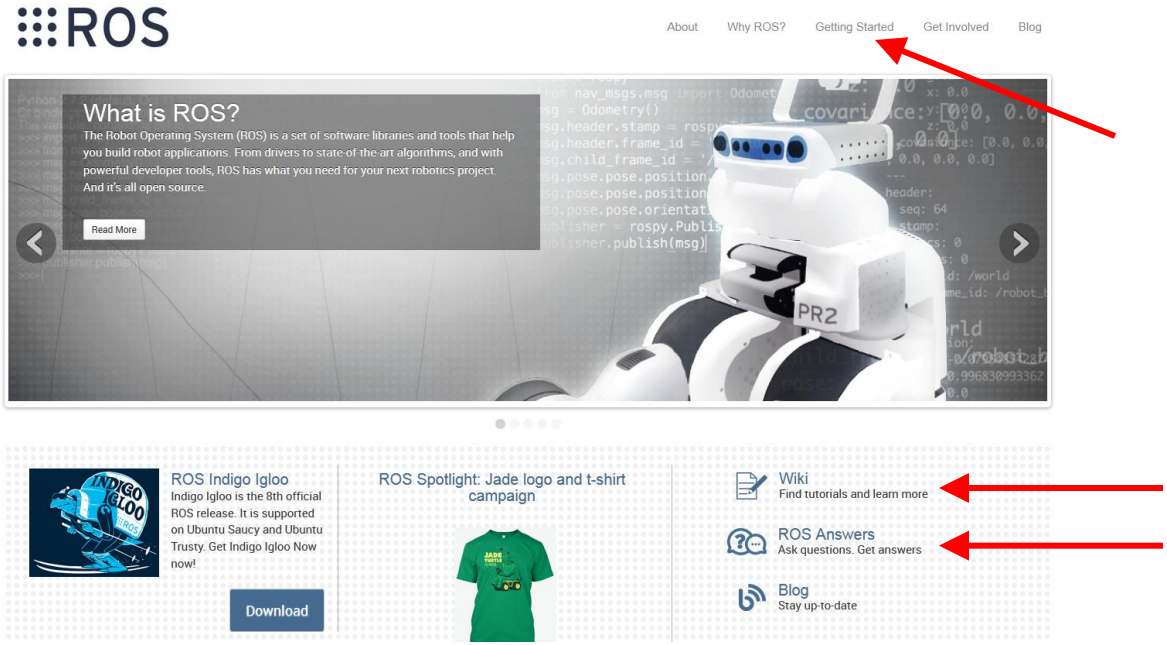
- Can intermix programming languages
  - currently: C++, Python, Lisp
  - We will be using C++ for our exercises

ROS Resources



ROS.org Website

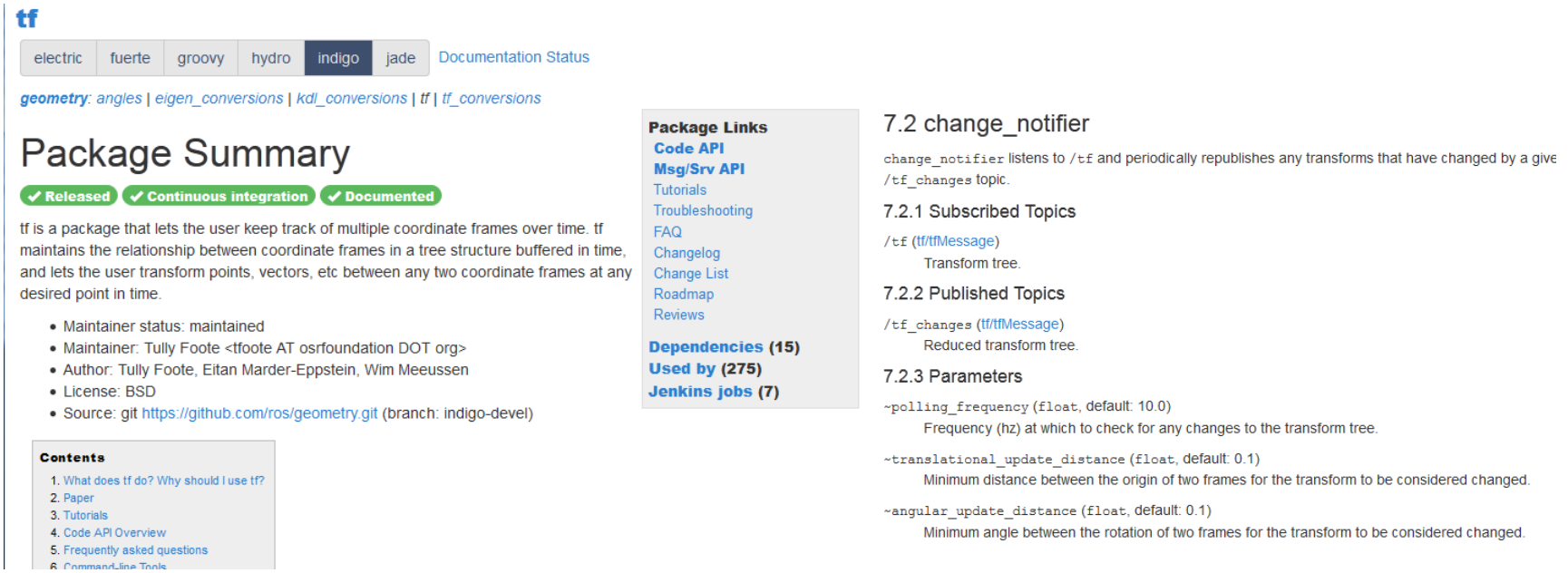
http://ros.org



- Install Instructions
- Tutorials
- Links
  - Packages, ROS Answers, etc.

Package Wiki

http://wiki.ros.org/<packageName>



tf

electric | fuerte | groovy | hydro | indigo | jade | Documentation Status

geometry: *angles* | *eigen_conversions* | *kdl_conversions* | *tf* | *tf_conversions*

Package Summary

✔ Released ✔ Continuous integration ✔ Documented

tf is a package that lets the user keep track of multiple coordinate frames over time. tf maintains the relationship between coordinate frames in a tree structure buffered in time, and lets the user transform points, vectors, etc between any two coordinate frames at any desired point in time.

- Maintainer status: maintained
- Maintainer: Tully Foote <tfoote AT osrfoundation DOT org>
- Author: Tully Foote, Eitan Marder-Eppstein, Wim Meeussen
- License: BSD
- Source: git https://github.com/ros/geometry.git (branch: indigo-devel)

Contents

1. What does tf do? Why should I use tf?
2. Paper
3. Tutorials
4. Code API Overview
5. Frequently asked questions

Package Links
Code API
Msg/Srv API
Tutorials
Troubleshooting
FAQ
Changelog
Change List
Roadmap
Reviews

Dependencies (15)
Used by (275)
Jenkins jobs (7)

7.2 change_notifier

`change_notifier` listens to `/tf` and periodically republishes any transforms that have changed by a give `/tf_changes` topic.

7.2.1 Subscribed Topics

`/tf` (tf/tfMessage)
Transform tree.

7.2.2 Published Topics

`/tf_changes` (tf/tfMessage)
Reduced transform tree.

7.2.3 Parameters

`~polling_frequency` (`float`, default: 10.0)
Frequency (hz) at which to check for any changes to the transform tree.

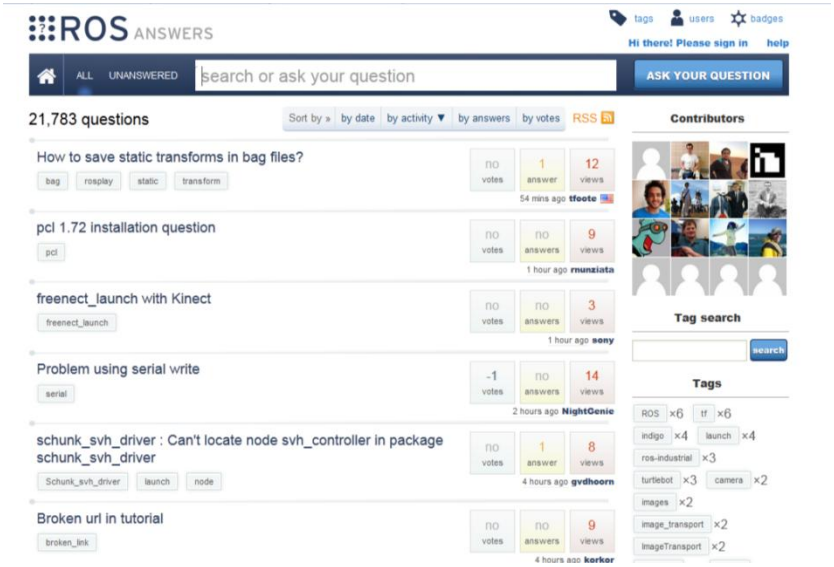
`~translational_update_distance` (`float`, default: 0.1)
Minimum distance between the origin of two frames for the transform to be considered changed.

`~angular_update_distance` (`float`, default: 0.1)
Minimum angle between the rotation of two frames for the transform to be considered changed.

- Description / Usage
- Tutorials
- Code / Msg API
- Source-Code link
- Bug Reporting

ROS Answers

http://answers.ros.org



- Quick responses to Good Questions
- Search by text or tag
- Don’t re-invent the wheel!

ROS is a Community

- No Central "Authority" for Help/Support
  - Many users can provide better (?) support
  - ROS-I Consortium can help fill that need

- Most ROS-code is open-source
  - can be reviewed / improved by everyone
  - we count on **YOU** to help ROS grow!

Installing ROS

Install options

Debian Packages

- Nearly “automatic”
- Recommended for end-users
- Stable
- Easy

Source Repositories

- Access “latest” code
- Most at Github.com
- More effort to setup
- Unstable*

Can mix both options, as needed

Install using Debian Packages

```
sudo apt-get install ros-distro-package
```

admin permissions	manage ".deb"	install new ".deb"	all ROS pkgs start with `ros-`	ROS distribution	ROS package name

Use "-" not "_"

- Fully automatic install:
  - Download .deb package from central ROS repository
  - Copies files to standard locations (`/opt/ros/indigo/...`)
  - ➢ Also installs any other required dependencies

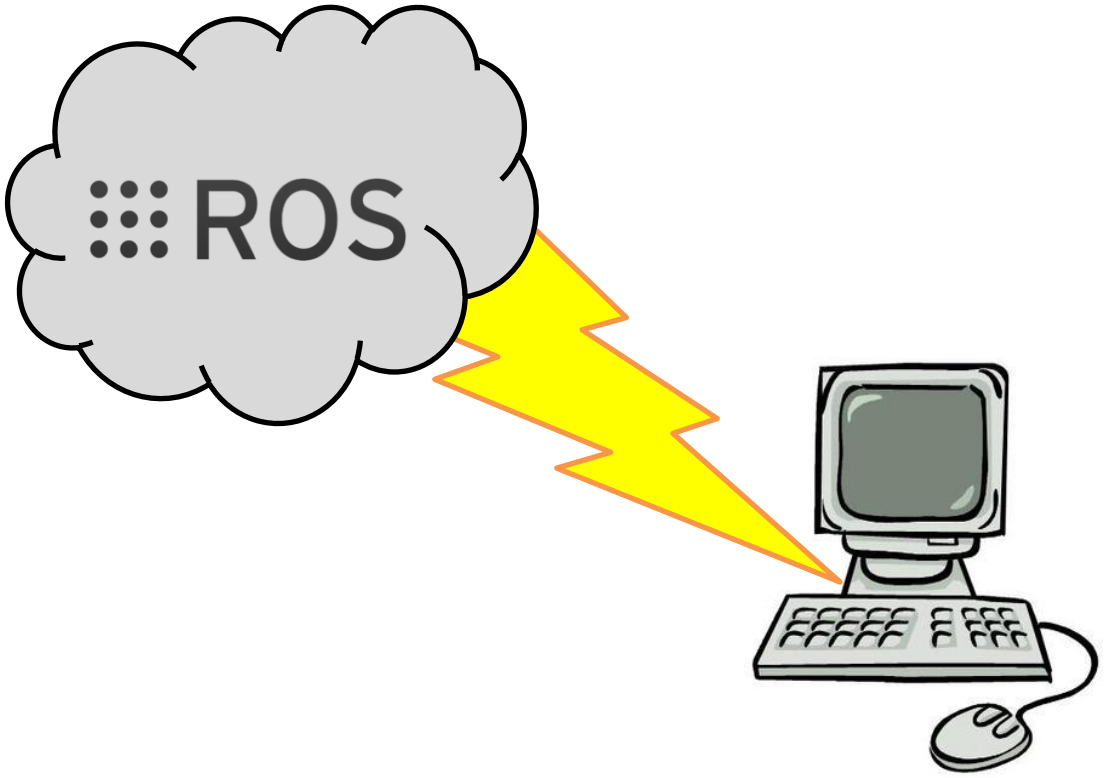
- `sudo apt-get remove ros-distro-package`
  - Removes software (but not dependencies!)

Finding the Right Package

- ROS Website (http://ros.org/browse/)
  - Browse/Search for known packages
- ROS Answers (http://answers.ros.org)
  - When in doubt... ask someone!
- `apt-cache search <search term>`
  - Searches titles and descriptions for search term

Exercise 1.1

Basic ROS Install/Setup



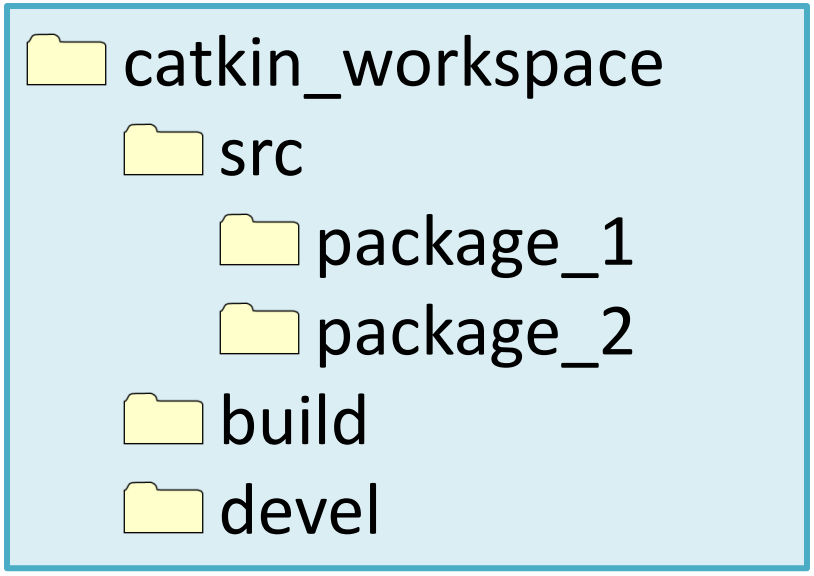
Installing from Source

- ROS uses the **catkin** build system
  - based on CMAKE
  - cross-platform (Ubuntu, Windows, embedded...)
  - replaces older **rosbuild** system
    - different build commands, directory structure, etc.
    - most packages have already been upgraded to catkin
    - rosbuild: `manifest.xml`, catkin: `package.xml`

http://www.clearpathrobotics.com/blog/introducing-catkin/

Catkin Workspace

- Catkin uses a specific directory structure:
  - each “project” typically gets its own **catkin workspace**
  - all source files go in the **src** directory
  - temporary build-files are created in **build**
  - results are placed in **devel**



Catkin Build Process

Setup (one-time)

1. Create a catkin workspace somewhere
   - `my_catkin_ws/src`
   - `build`, `devel` directories created automatically
2. Run `catkin_init_workspace` in `src` subdir
3. Download/create **packages** in `src` subdir

Compile-Time

1. Run `catkin_make` in **workspace root**
2. Run `source devel/setup.bash` to make workspace visible to ROS
   - Must re-execute in **each** new terminal window
   - Most ROS-I training units automate this process

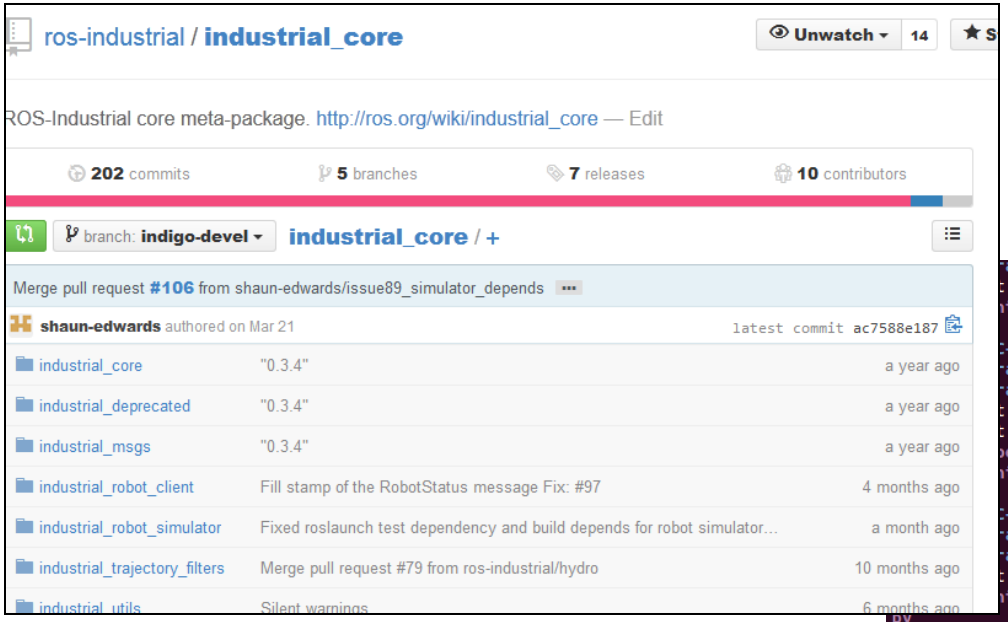
Training Exercise Layout

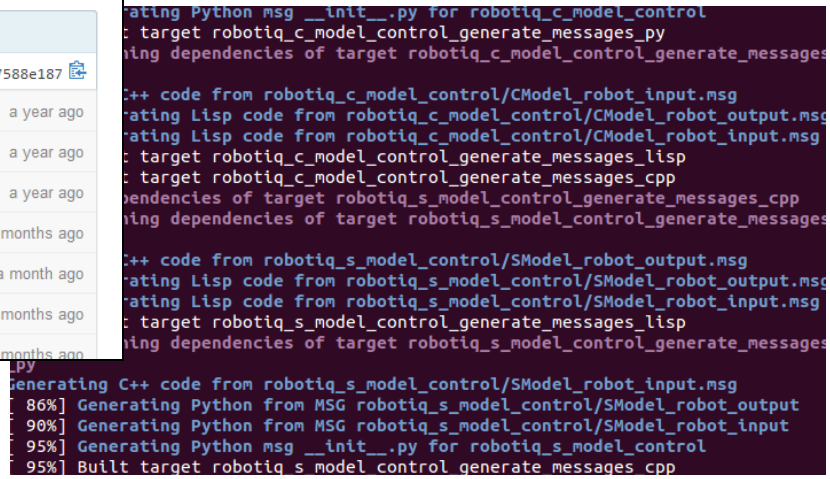
- ~/industrial_training/training
  - work
    - 1.2
    - 1.3
      - src
      - build
      - devel
  - orig
    - 1.2
    - 1.3
  - ref
    - 1.2
    - 1.3

- Main sub-directories:
  - **work** : working area
  - **orig** : copy of “work”
  - **ref** : completed exercises
- `training_unit 1.2`
  - change directory
  - catkin_make
  - source catkin workspace
- Also:
  - `training_ref 1.2`
  - `clear_training_unit`

Exercise 1.2

Install from Source

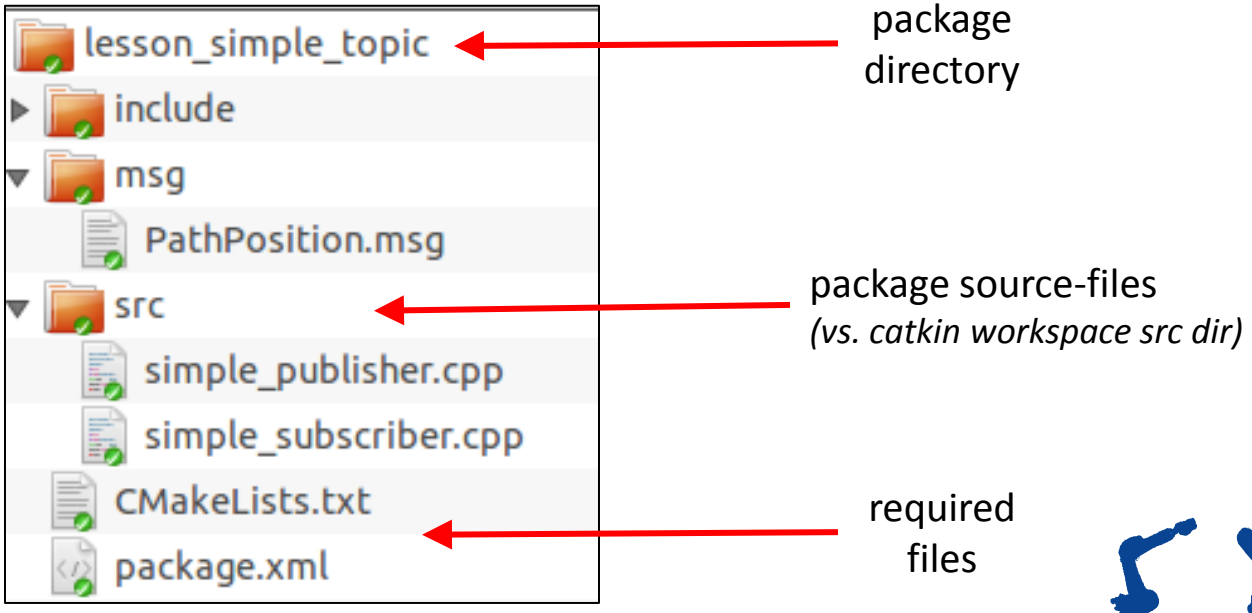




ROS Packages

ROS Package Contents

- ROS components are organized into **packages**
- Packages contain several **required files**:
  - `package.xml`
    - **metadata** for ROS: package name, description, dependencies, ...
  - `CMakeLists.txt`
    - **build rules** for catkin



package.xml

- Metadata: name, description, author, license ...

```
<package>
  <name>lesson_simple_parameters</name>
  <version>0.0.0</version>
  <description>The lesson_simple_parameters package</description>

  <!-- One maintainer tag required, multiple allowed, one person per tag -->
  <!-- Example:  -->
  <!-- <maintainer email="jane.doe@example.com">Jane Doe</maintainer> -->
  <maintainer email="jane.doe@example.com">Jane Doe</maintainer>


  <!-- One license tag required, multiple allowed, one license per tag -->
  <!-- Commonly used license strings: -->
  <!--   BSD, MIT, Boost Software License, GPLv2, GPLv3, LGPLv2.1, LGPLv3 -->
  <license>BSD</license>
```

package.xml

- Metadata: name, description, author, license ...
- Dependencies:
  - `<build_depend>` – needed to **compile** package
  - `<run_depend>` – needed to **run** package

```
<build_depend>roscpp</build_depend>
<build_depend>industrial_robot_client</build_depend>
<build_depend>simple_message</build_depend>

<run_depend>roscpp</run_depend>
<run_depend>industrial_robot_client</run_depend>
```

CMakeLists.txt

- Provides **rules** for **building software**
  - template file contains many examples

```
include_directories(include ${catkin_INCLUDE_DIRS})
```

Adds directories to CMAKE include rules

```
add_executable(myNode src/myNode.cpp src/widget.cpp)
```

Builds program `myNode`, from `myNode.cpp` and `widget.cpp`

```
target_link_libraries(myNode ${catkin_LIBRARIES})
```

Links node `myNode` to dependency libraries

Create New Package

```
catkin-create-pkg pkg_name dep1 dep2
```

Easiest way to start a new package

- create directory, required files
- `pkg_name` : name of package to be created
- `dep1/2` : dependency package names
  - automatically added to `CMakeLists` and `package.xml`
  - can manually add additional dependencies later

ROS Package Commands

- `roscd package_name`

  Change to package directory

- **`rospack`**
  - `rospack find package_name`

    Find directory of `package_name`
  - `rospack list`

    List all ros packages installed
  - `rospack depends package_name`

    List all dependencies of `package_name`

Nodes

A Simple C++ ROS Node

Simple C++ Program

```
int main(int argc, char* argv[])
{
    std::cout << "Hello World!";

    return 0;
}
```

Simple C++ ROS Node

```
#include <ros/ros.h>

int main(int argc, char* argv[])
{
  ros::init(argc, argv, "hello");
  ros::NodeHandle node;

  ROS_INFO_STREAM("Hello World!");

  return 0;
}
```

ROS Node Commands

- `rosrun package_name node_name`

  execute ROS node

- **`rosnode`**
  - `rosnode list`

    View running nodes
  - `rosnode info node_name`

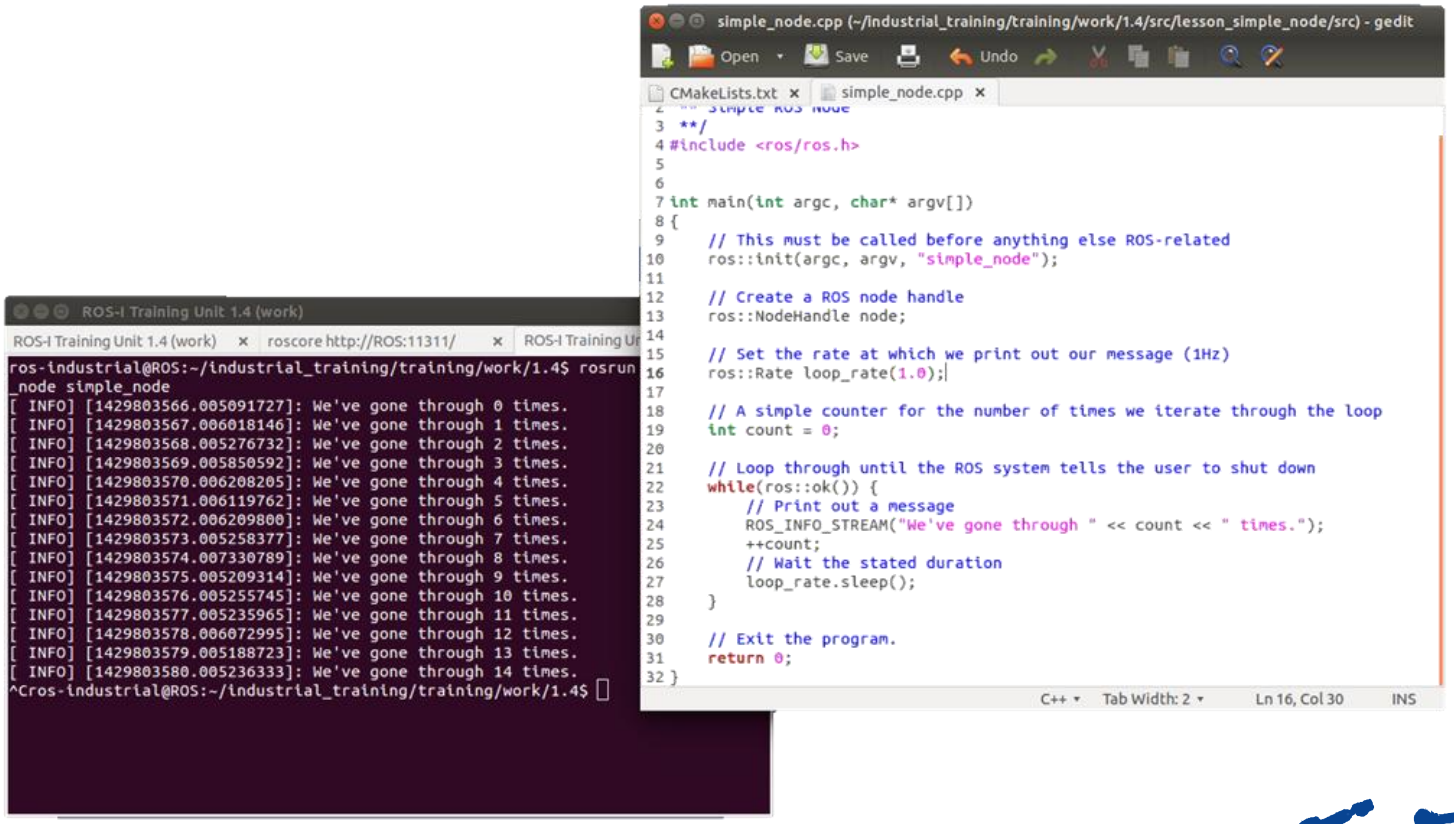
    View node details (publishers, subscribers, services, etc.)
  - `rosnode kill node_name`

    Kill running node

    ➢ `Ctrl+C` *is usually easier*

Exercise 1.4

Running a Node

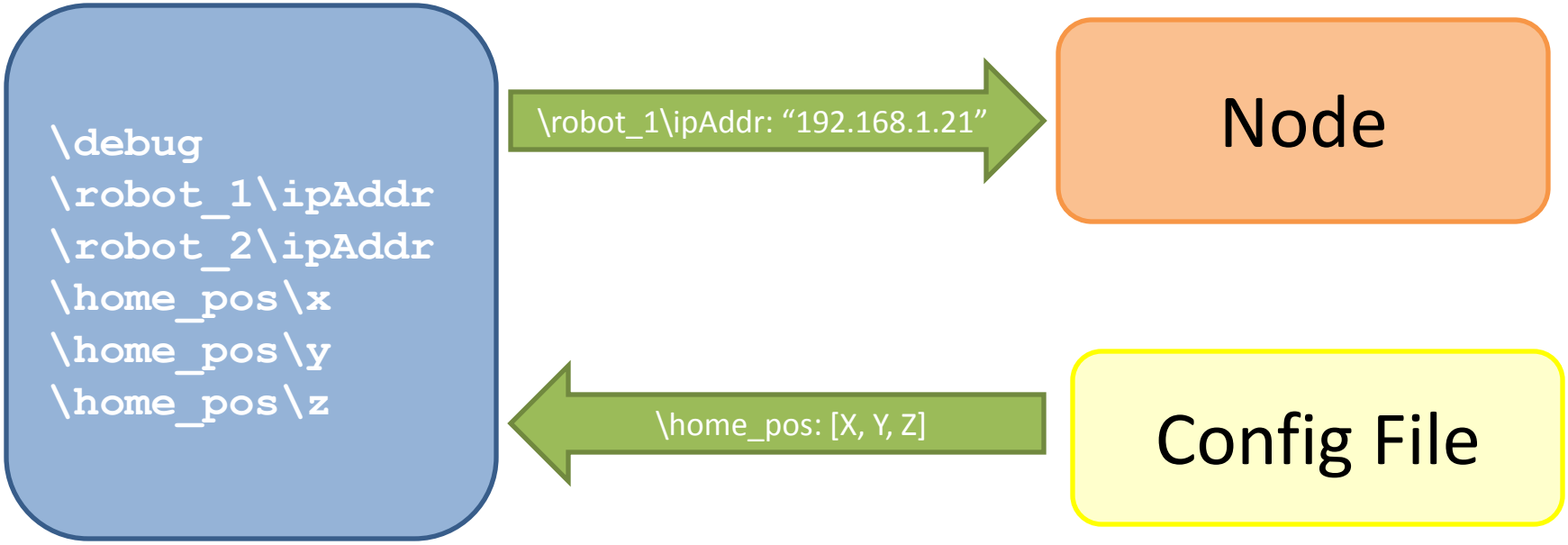


Parameters

Parameters: Overview

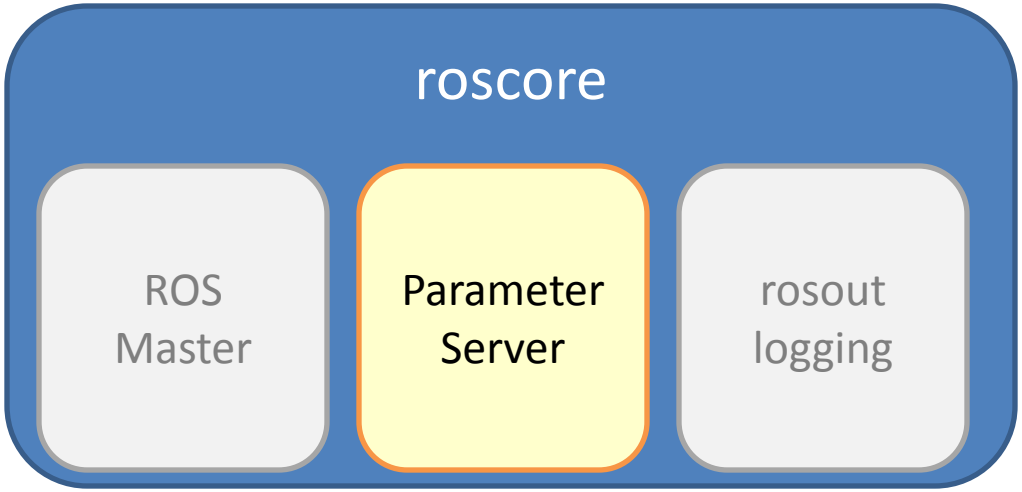
Parameters are like **Global Data**

Parameter Server



ROS Parameters

- Typically configuration-type values
  - robot kinematics
  - workcell description
  - algorithm limits / tuning
- Accessed through the **Parameter Server**.
  - *Typically handled by **roscore***



Setting Parameters

- Can set from:
  - YAML Files

```
manipulator_kinematics:
  solver: kdl_plugin/KDLKinematics
  search_resolution: 0.005
  timeout: 0.005
  attempts: 3
```

  - Command Line

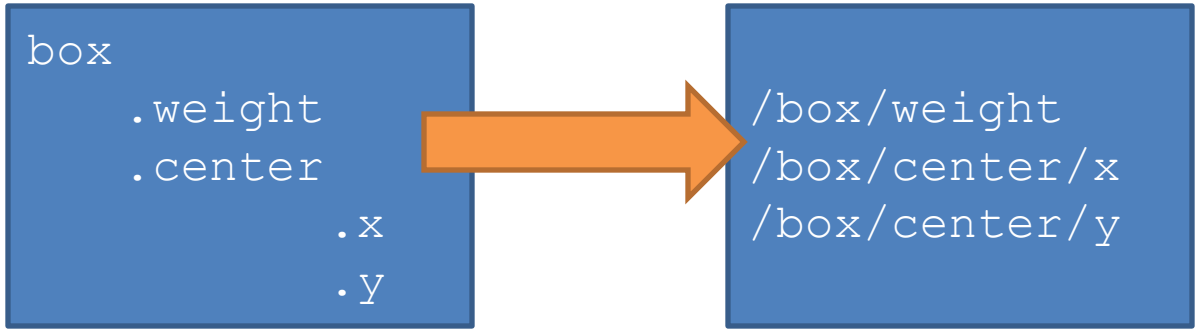
```
rosrun my_pkg load_robot _ip:="192.168.1.21"
rosparam set "/debug" true
```

  - Programs

```
nh.setParam("name", "left");
```

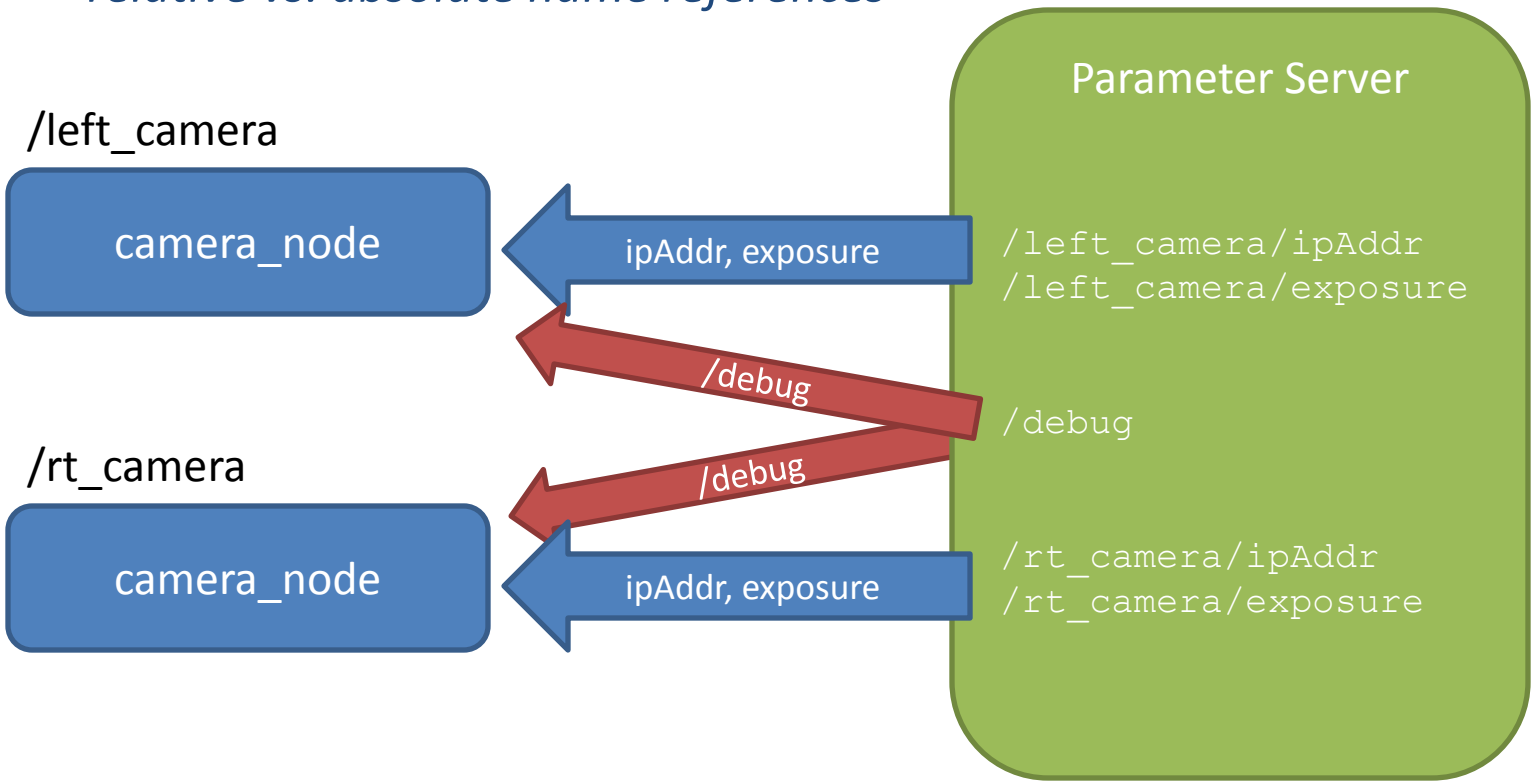
Parameter Datatypes

- Native Types
  - *int, real, boolean, string*
- Lists (vectors)
  - *can be mixed type: [1, str, 3.14159]*
  - *but typically of single type: [1.1, 1.2, 1.3]*
- Dictionaries (structures)
  - *translated to "folder" hierarchy on server*



Namespaces

- Folder Hierarchy allows Separation:
  - *Separate nodes can co-exist, in different "namespaces"*
  - *relative vs. absolute name references*



Parameter Commands

- **`rosparam`**
  - `rosparam set <key> <value>`
    - Set parameters
  - `rosparam get <key>`
    - Get parameters
  - `rosparam delete <key>`
    - Delete parameters
  - `rosparam list`
    - List all parameters currently set
  - `rosparam load <filename> [<namespace>]`
    - Load parameters from file

Parameters: C++ API

- Accessed through `ros::NodeHandle` object
  - also sets default **Namespace** for access
    - Global (root) namespace:

```
ros::NodeHandle global();
global.getParam("test");
```

"/test"

    - Fixed namespace:

```
ros::NodeHandle fixed("/myApp");
global.getParam("test");
```

"/myApp/test"

    - Private namespace:

```
ros::NodeHandle priv("~");
global.getParam("test");
```

"/myNode/test"

Parameters: C++ API (cont'd)

- `NodeHandle` object methods
  - `nh.hasParam(key)`

    Returns true if parameter exists
  - `nh.getParam(key, &value)`

    Gets value, returns T/F if exists.
  - `nh.param(key, &value, default)`

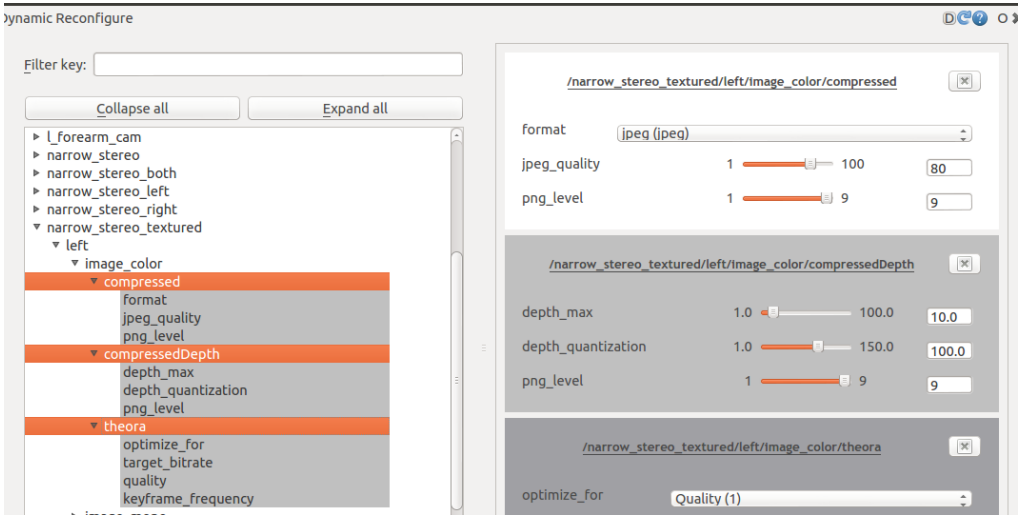
    Get value (or default, if doesn't exist)
  - `nh.setParam(key, value)`

    Sets value
  - `nh.deleteParam(key)`

    Deletes parameter

Dynamic reconfigure

- Parameters must be read explicitly by nodes
  - no on-the-fly updating
  - typically read only when node first started
- ROS package `dynamic_reconfigure` can help
  - nodes can register callbacks to trigger on change
  - outside the scope of this class, but useful



Exercise 1.5

ROS Parameters

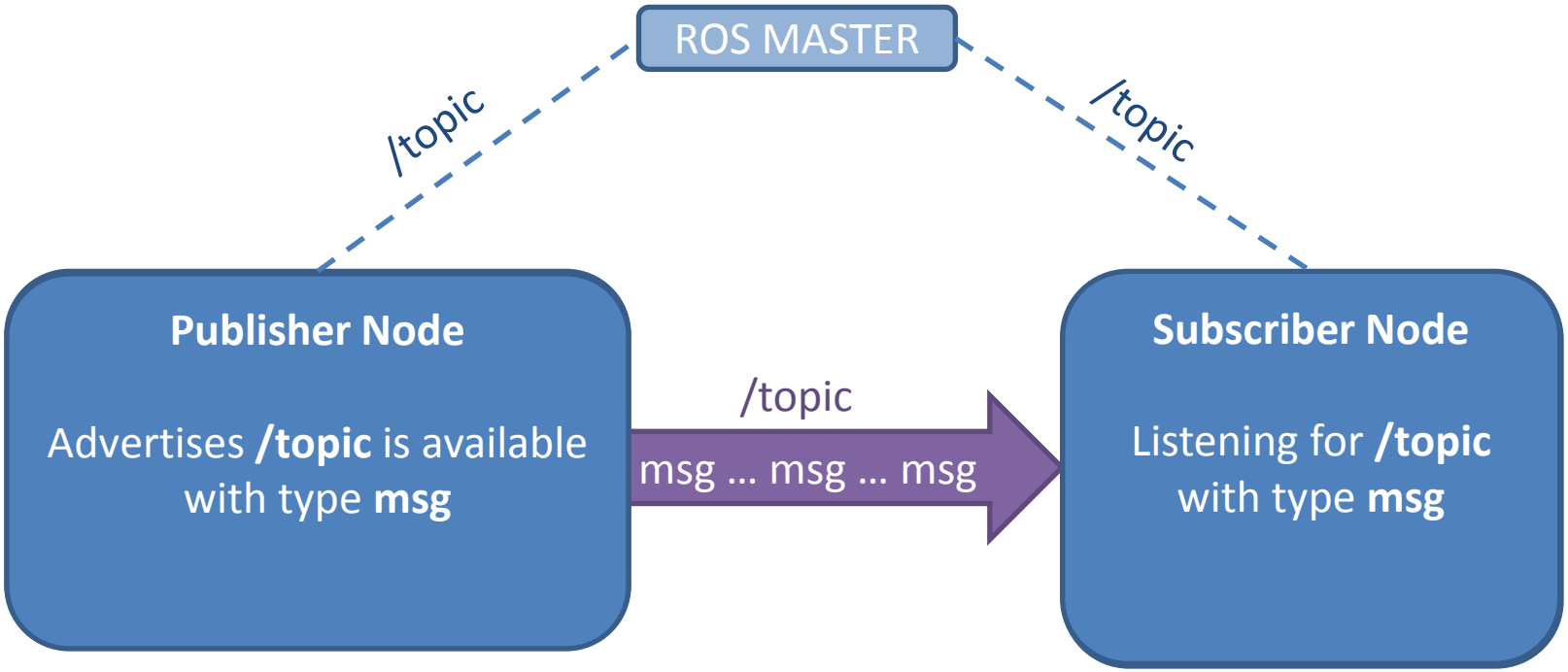
watch as I walk through this example...

```
/global_integer_value
/rosdistro
/roslaunch/uris/host_ros_industrial_
/rosversion
/run_id
/simple_parameters/integer_value
/simple_parameters/point/x
/simple_parameters/point/y
/simple_parameters/simple_string
```

Topics and Messages

ROS Topics/Messages

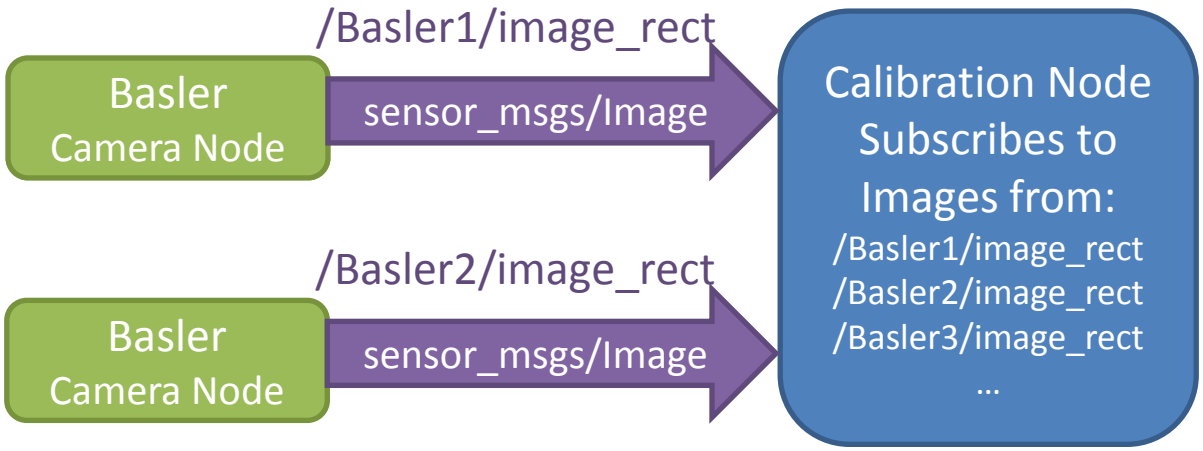
Topics are for **Streaming Data**



Topics vs. Messages

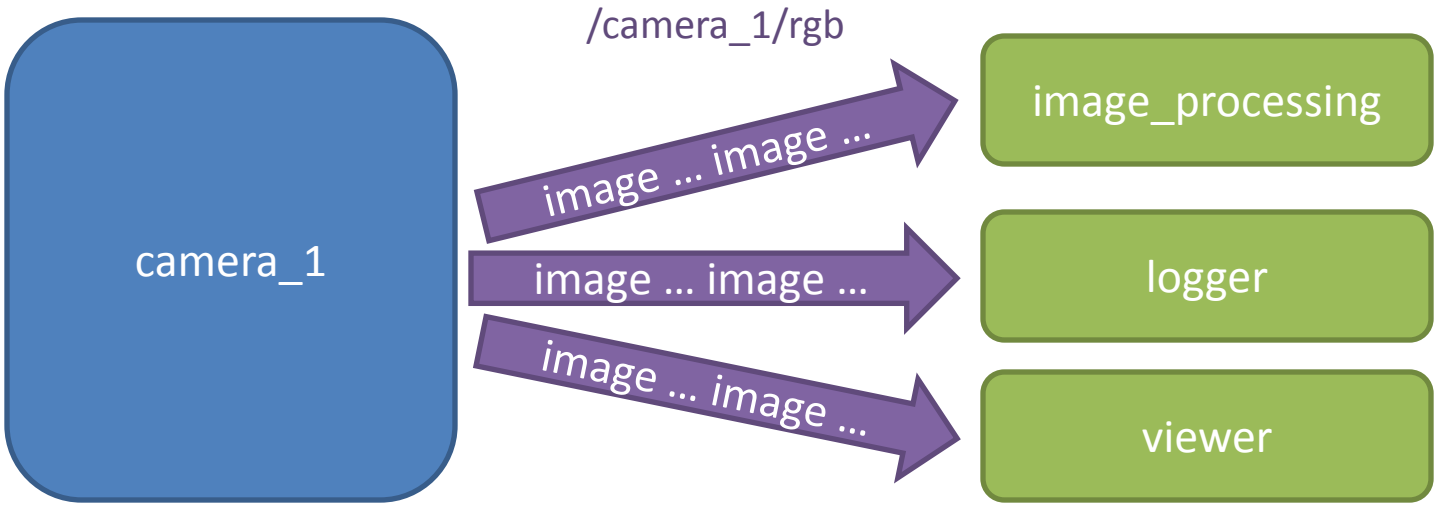
- Topics are **channels**, Messages are **data types**
  - Different topics can use the same Message type

Practical Example



Multiple Pub/Sub

- Many nodes can pub/sub to same topic
  - comms are direct node-to-node



Topics : Details

- Each **Topic** is a stream of **Messages**:
  - sent by **publisher(s)**, received by **subscriber(s)**
- Messages are **asynchronous**
  - publishers don't know if anyone's listening
  - messages may be dropped
  - subscribers are event-triggered (by incoming messages)
- Typical Uses:
  - Sensor Readings: camera images, distance, I/O
  - Feedback: robot status/position
  - Open-Loop Commands: desired position

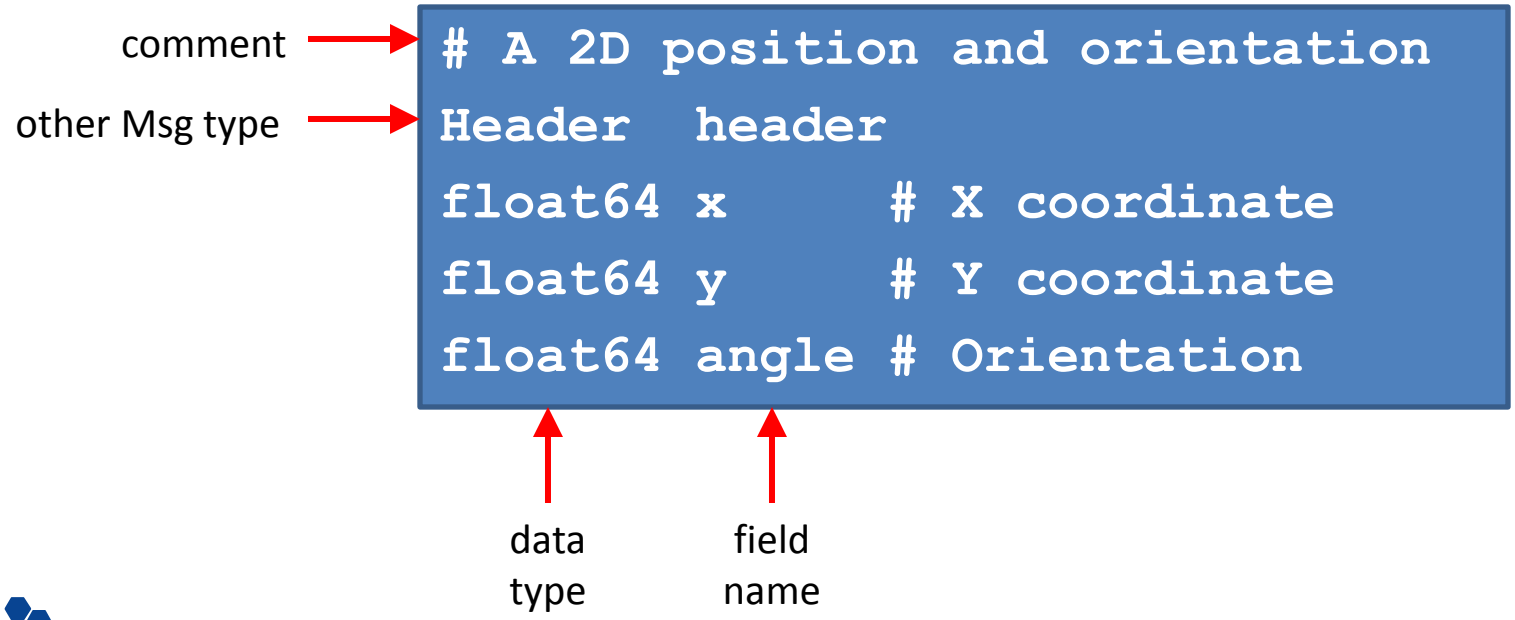
ROS Messages Types

- Similar to C structures
- Standard data primitives
  - Boolean: `bool`
  - Integer: `int8, int16, int32, int64`
  - Unsigned Integer: `uint8, uint16, uint32, uint64`
  - Floating Point: `float32, float64`
  - String: `string`
- Fixed length arrays: `bool[16]`
- Variable length arrays: `int32[]`
- Other: Nest message types for more complex data structure

Message Description File

- All Messages are defined by a **.msg** file

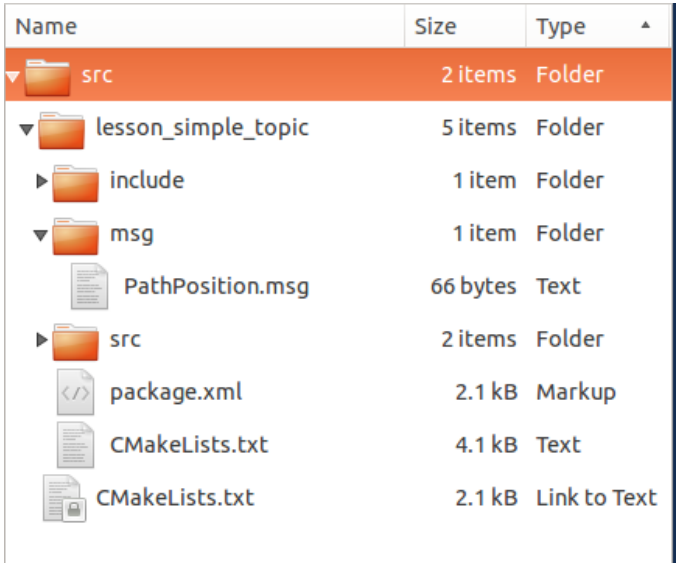
PathPosition.msg



Custom ROS Messages

- Custom message types are defined in `msg` subfolder of packages

- Modify `CMakeLists.txt` to enable message generation.



ROS Message Commands

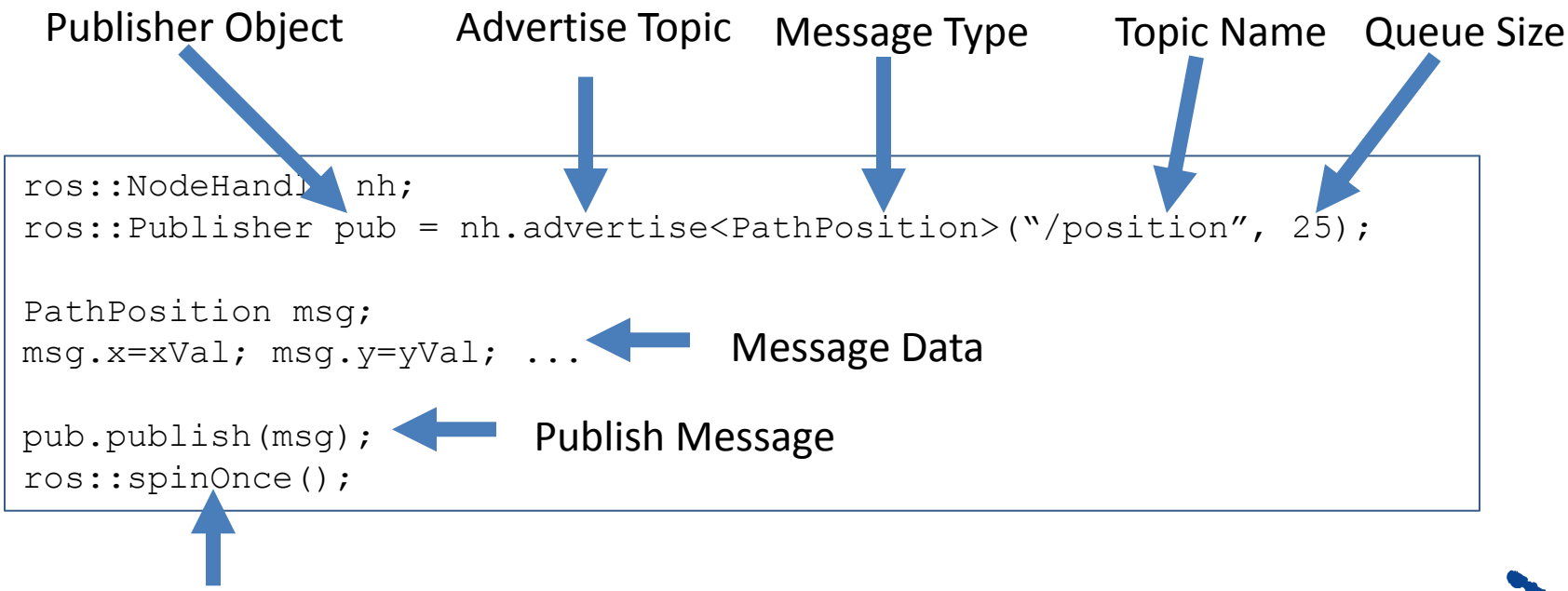
- `rosmsg list`
  - Show all ROS topics currently installed on the system
- `rosmsg package <package>`
  - Show all ROS message types in package `<package>`
- `rosmsg show <package>/<message_type>`
  - Show the structure of the given message type

ROS Topic Commands

- `rostopic list`
  - List all topics currently subscribed to and/or publishing
- `rostopic type <topic>`
  - Show the message type of the topic
- `rostopic info <topic>`
  - Show topic message type, subscribers, publishers, etc.
- `rostopic echo <topic>`
  - Echo messages published to the topic to the terminal
- `rostopic find <message_type>`
  - Find topics of the given message type

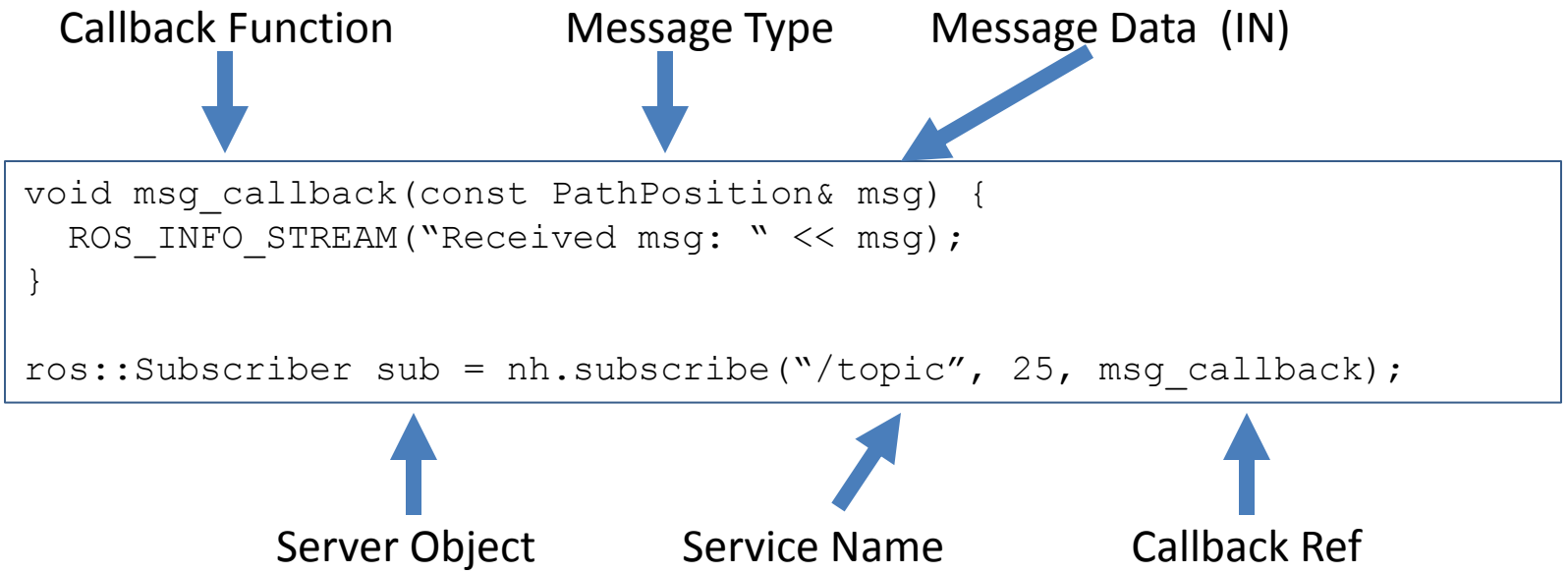
Topics: Syntax

- Topic **Publisher**
  - Advertises available topic *(Name, Data Type)*
  - Populates message data
  - Periodically publishes new data



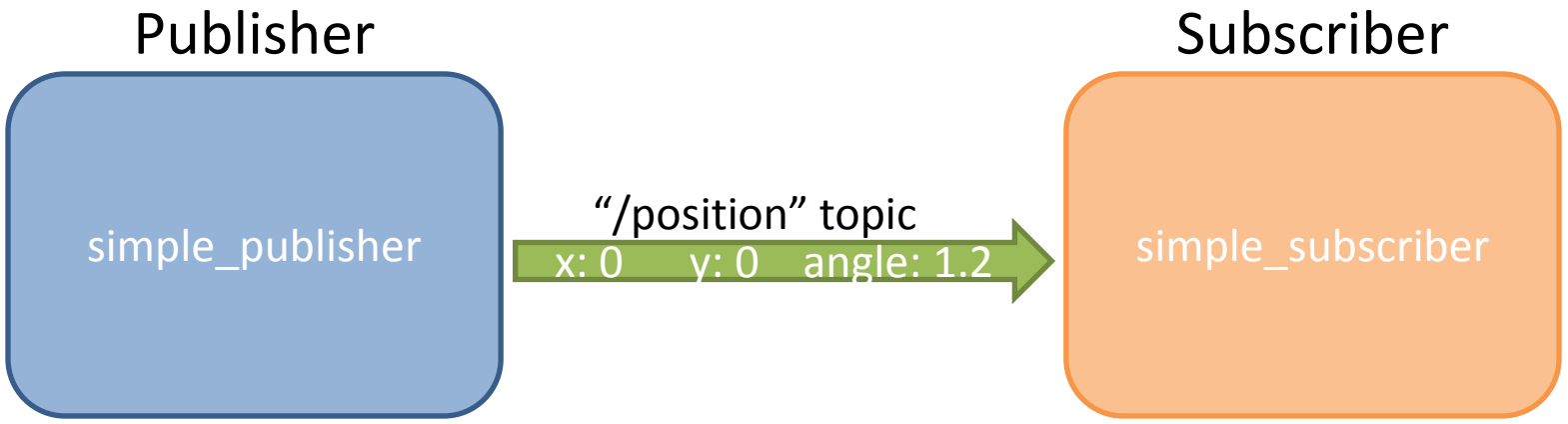
Topics: Syntax

- Topic **Subscriber**
  - Defines callback function
  - Listens for available topic *(Name, Data Type)*



Exercise 1.6

ROS Topics and Messages



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