COMP.4510/COMP.5490 Mobile Robotics
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Introduction to ROS

Setting Up Your ROS Workspace

Go to http://wiki.ros.org/catkin/Tutorials/create_a_workspace . Select "*indigo*". Follow the instructions to create and configure your catkin_ws.

Creating a ROS Package

Create a ROS package : http://wiki.ros.org/ROS/Tutorials/CreatingPackage . When you run "catkin_create_pkg", use the -m option:

catkin_create_pkg ***-m [your name]*** [pkg name] roscpp rospy std_msgs

ROS "Hello World"

Now you will create basic publisher and subscriber nodes:
Got to http://wiki.ros.org/ROS/Tutorials/WritingPublisherSubscriber%28python%29 (Python) OR to http://wiki.ros.org/ROS/Tutorials/WritingPublisherSubscriber%28c%2B%2B%29 (C/C++)

Running Nodes

Go to http://wiki.ros.org/ROS/Tutorials/ExaminingPublisherSubscriber to run your nodes. Experiment with them.

- What happens if you run "rostopic list"?
- How about "rostopic hz /chatter"?
- What happens if you [CTRL]-C the publisher while the subscriber is still running?
- What if you shut down the roscore while the other nodes are running?