

Ros2

@theconstruct.ai

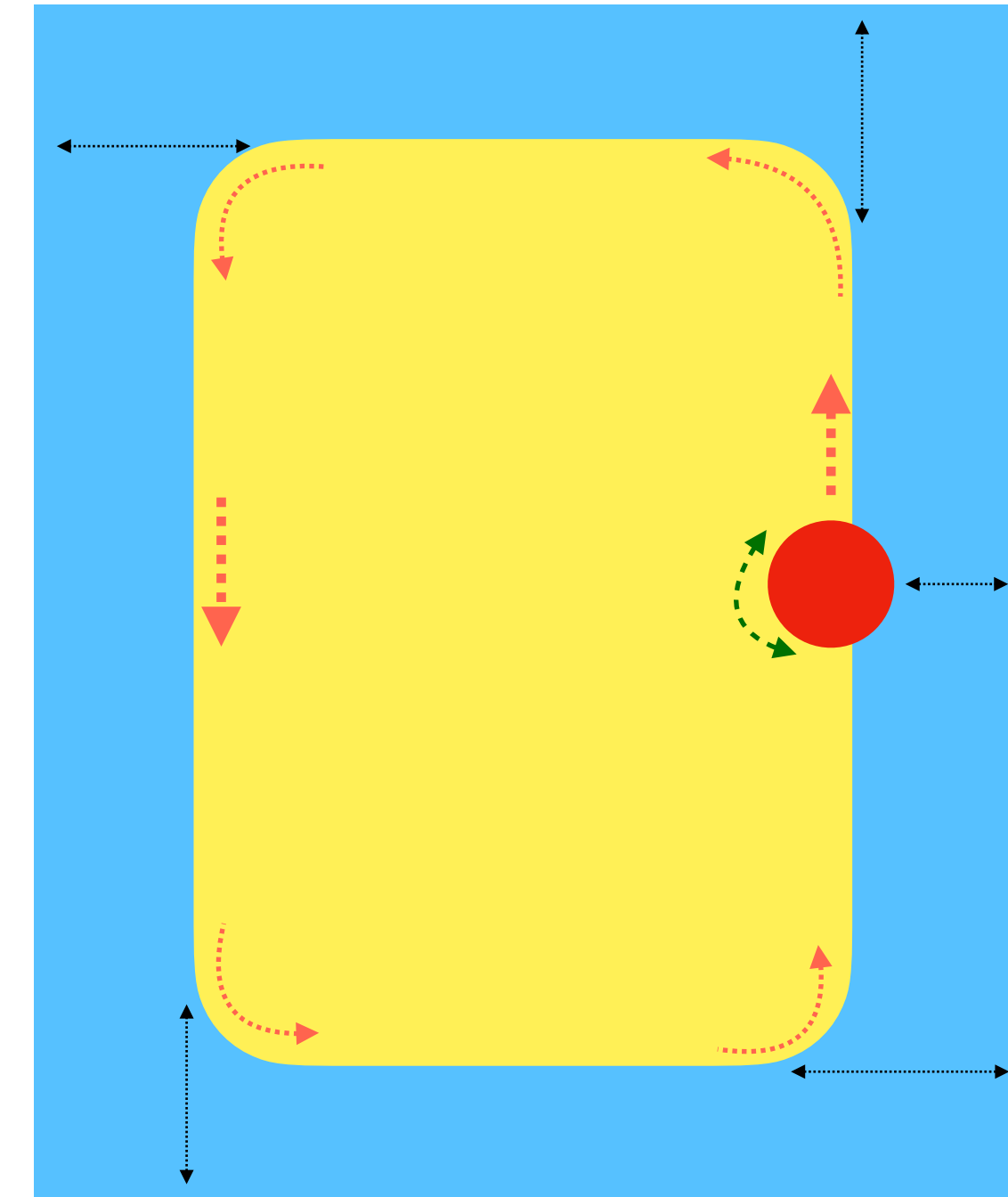
Agenda

- Basics
 - Micro project
 - Pub sub model, Services, Actions
 - Demo
- URDF

Basics

Micro Project

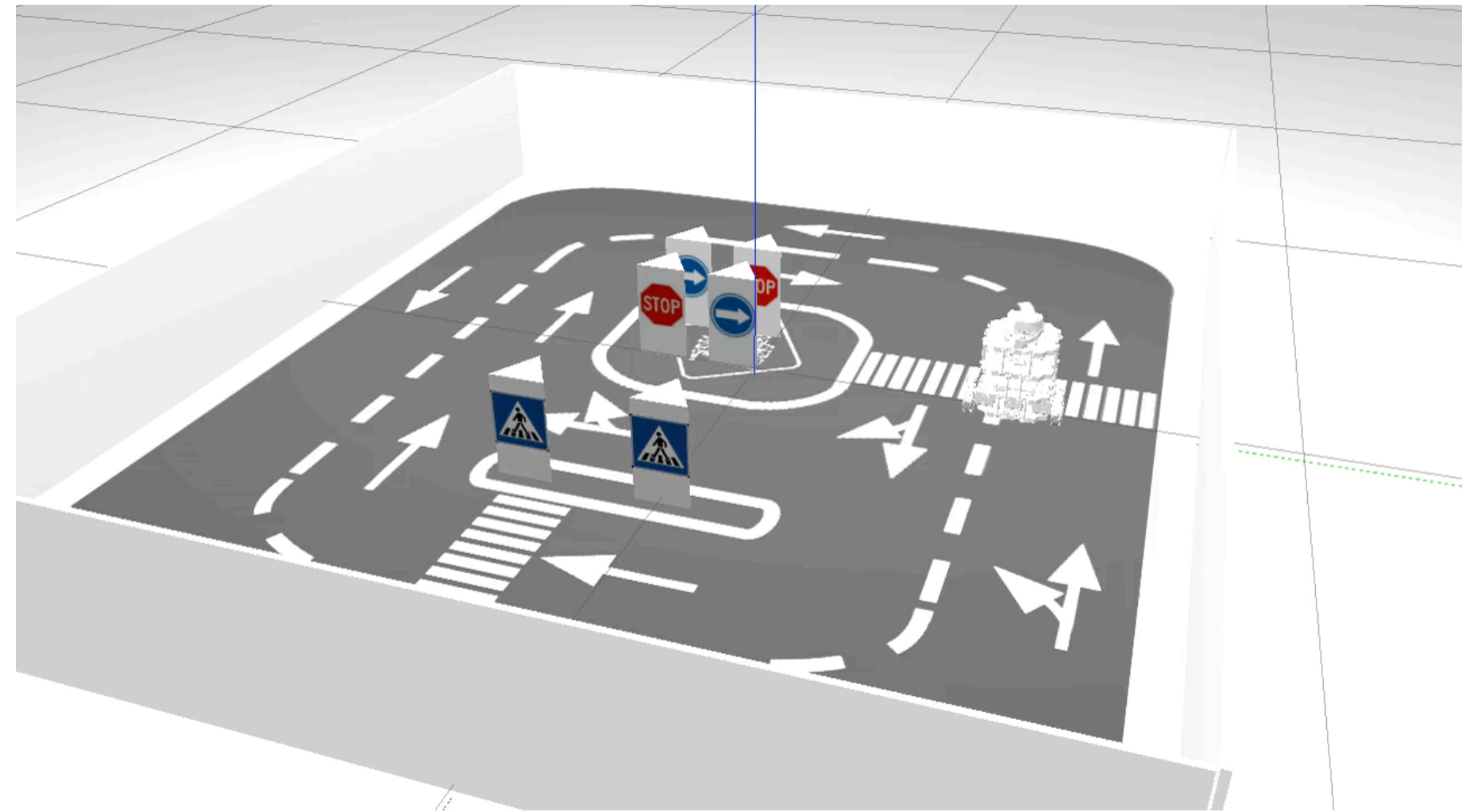
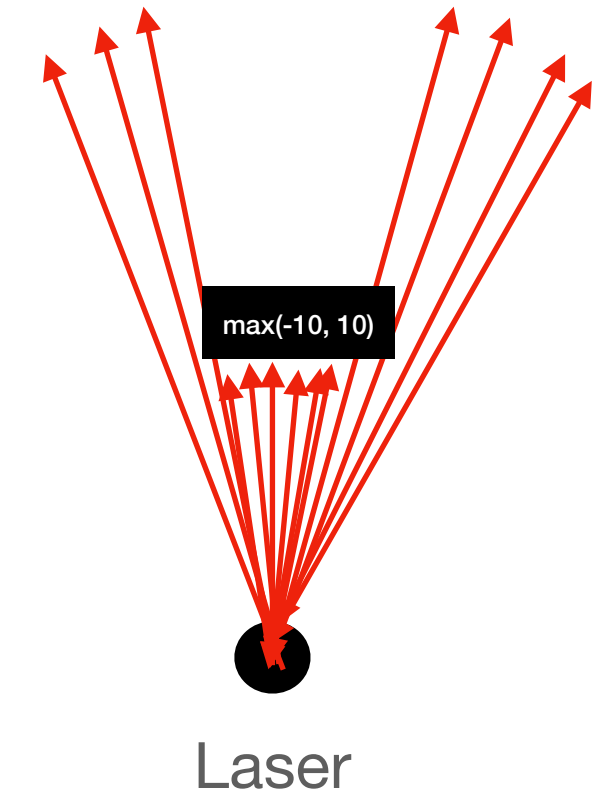
- Detect a wall using scan data
- Get near the wall
- Rotate for forward movement
- Move + detect obstacles
- Turn left where necessary
- Compute distance travelled
- Stop at 1 lap if near start point



Basics

Micro Project

- **Detects the nearest wall** using laser scan data and rotates to face it.
- **Moves forward** until it reaches a safe distance from the wall.
- **Aligns with the wall** by rotating to a 270° orientation.
- **Sends movement commands** to align with a detected wall using laser scan data.
- **Interacts with an action server** to record odometry and retrieve position data.
- **Publishes velocity commands** to navigate safely while maintaining an appropriate distance.
- **Records odometry data** and calculates total distance traveled using position updates.
- **Implements an action server** to track movement, provide feedback, and handle goal execution.
- **Detects laps based on distance** from the starting point and publishes updates accordingly.



Basics

Micro Project

sensor_msgs/LaserScan

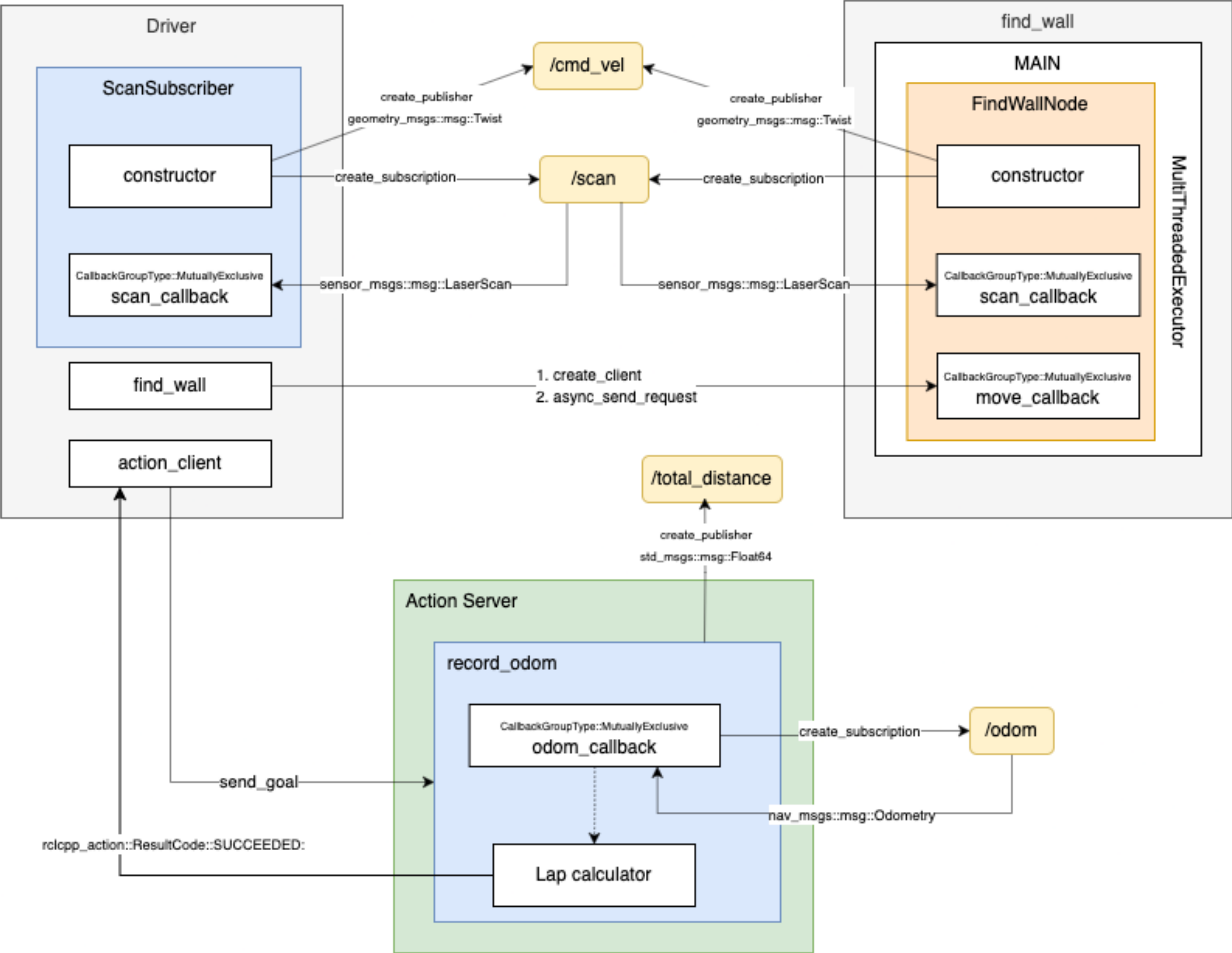
```
std_msgs/Header header
float32 angle_min
float32 angle_max
float32 angle_increment
float32 time_increment
float32 scan_time
float32 range_min
float32 range_max
float32[] ranges
float32[] intensities
```

geometry_msgs/Twist

```
geometry_msgs/Vector3 linear
geometry_msgs/Vector3 angular
```

nav_msgs/Odometry.msg

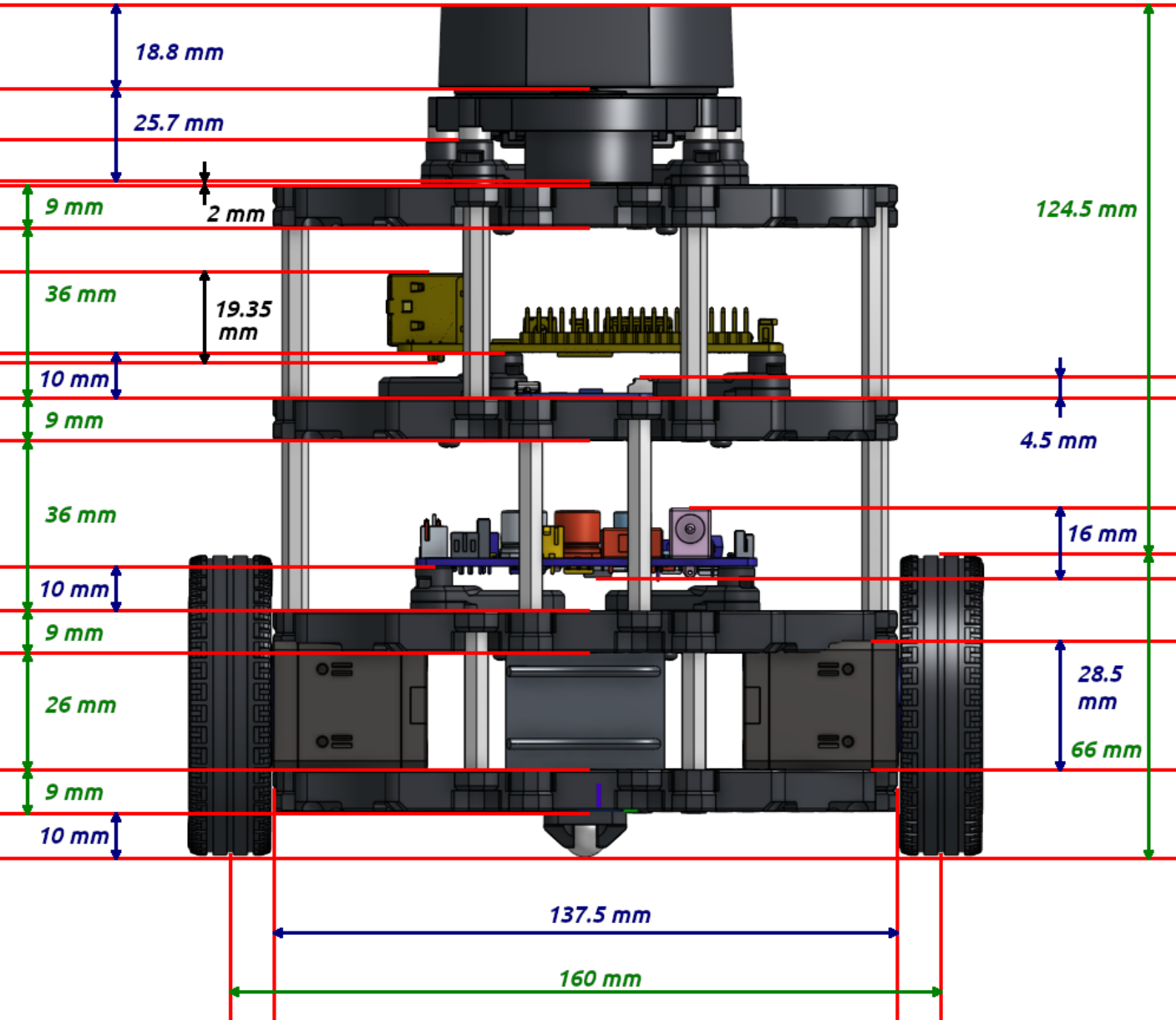
```
std_msgs/Header header
string child_frame_id
geometry_msgs/PoseWithCovariance pose
geometry_msgs/TwistWithCovariance twist
```



URDF

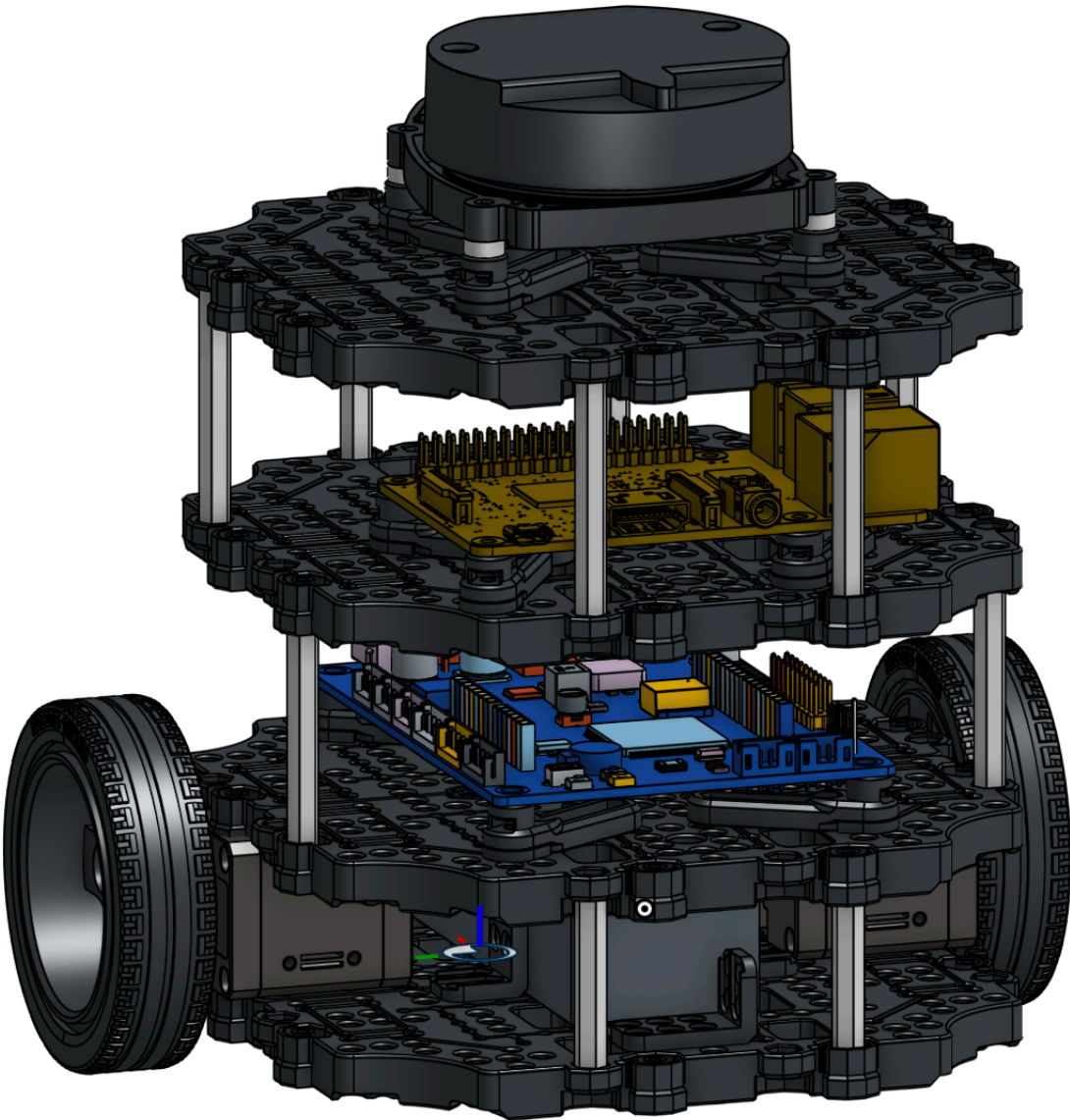
Micro Project

- Construct the Turtlebot 3 in **UDRF/Xacro** using specs below
- Conditionally load** Gazebo items based on launch paramters



TurtleBot3 Burger Parts Specification

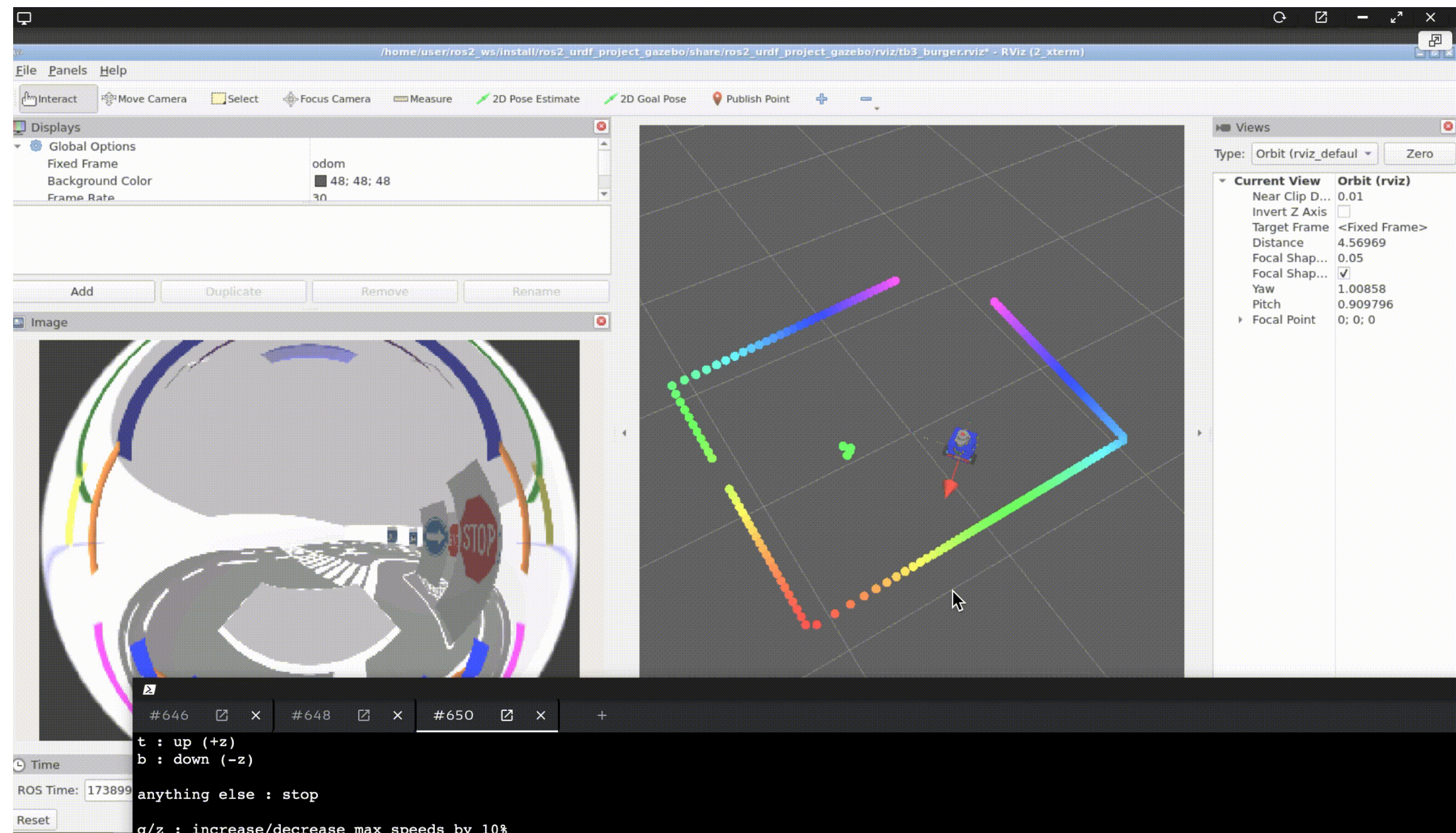
Part Name	Units	Unit Weight	Total Weight	Dimensions
Chassis Plate	4x	35g	140g	137.5mm x 137.5mm x 9mm
35mm Spacer	4x	7g	28g	5mm dia x 35mm
45mm Spacer	10x	9g	90g	5mm dia x 45mm
PCB Mounts	12x	5g	60g	37.82mm x 10mm x 10mm
Drive Motor	2x	50g	100g	46.5mm x 34mm x 28.5mm
Drive Wheel Axle	2x	10g	20g	20.5mm dia x 9.35mm
Drive Wheel & Tire Set	2x	25g	50g	66mm dia x 17.8mm
Caster Wheel Support	1x	10g	10g	30mm x 18mm x 8mm
Caster Wheel	1x	10g	10g	10mm dia
Control Board	1x	60g	60g	105mm x 75mm x 16mm
IMU Chip (<i>imu_link</i>)	1x	2g	2g	5mm x 5mm x 2.5mm
Raspberry Pi Board	1x	50g	50g	58mm x 90mm x 19.35mm
Lidar USB Board	1x	10g	10g	18mm x 30mm x 4.5mm
Camera Support	1x	10g	10g	5mm x 30mm x 15mm
Camera	1x	10g	10g	5mm x 30mm x 30mm
Lidar Support	1x	100g	100g	94.7mm x 72.7mm x 25.7mm
Lidar Spinner	1x	50g	50g	65.4mm dia x 18.8mm
Battery	1x	200g	200g	100mm x 35mm x 27.5mm
---	---	Total:	1000g	---



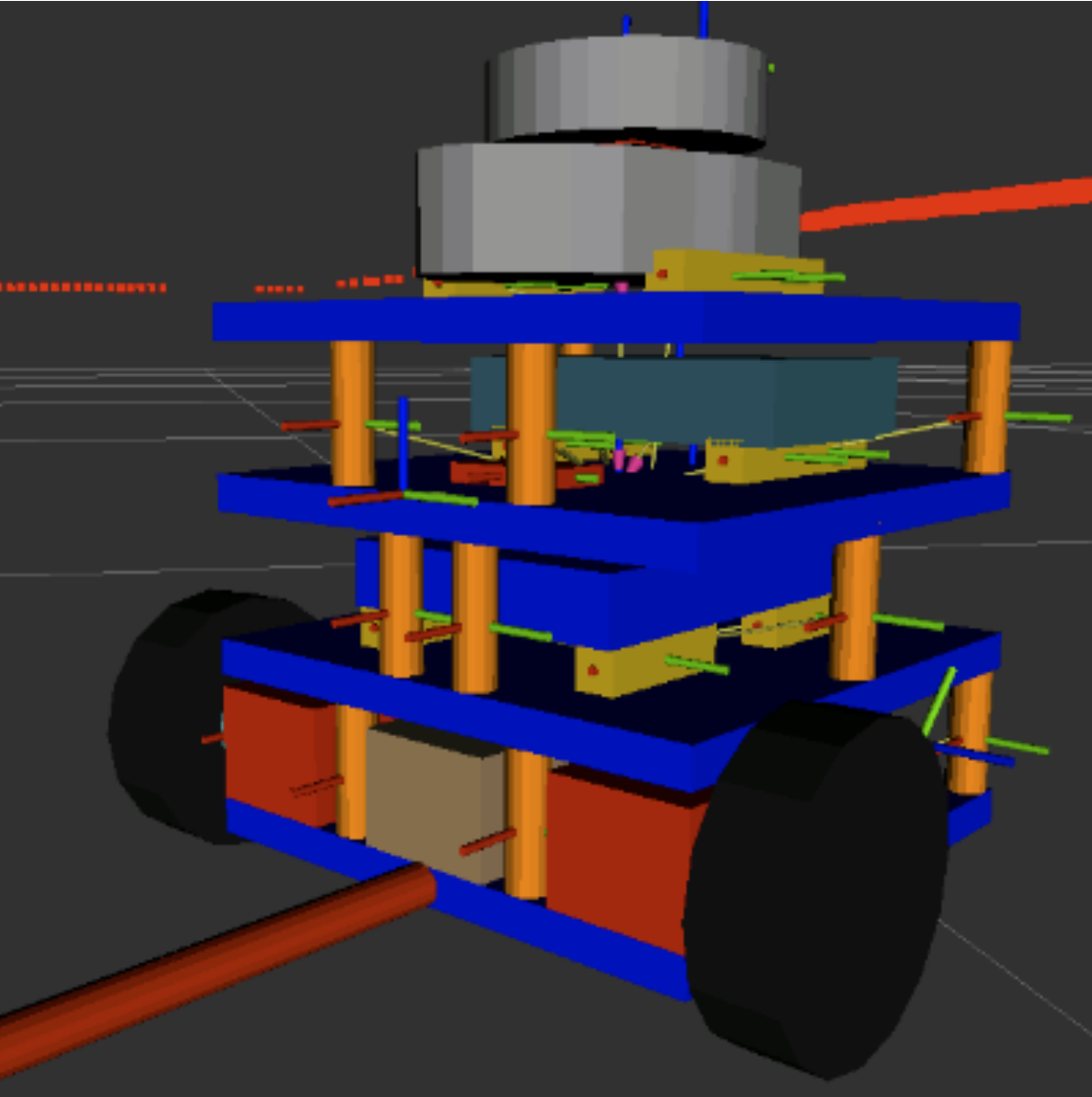
URDF

Micro Project

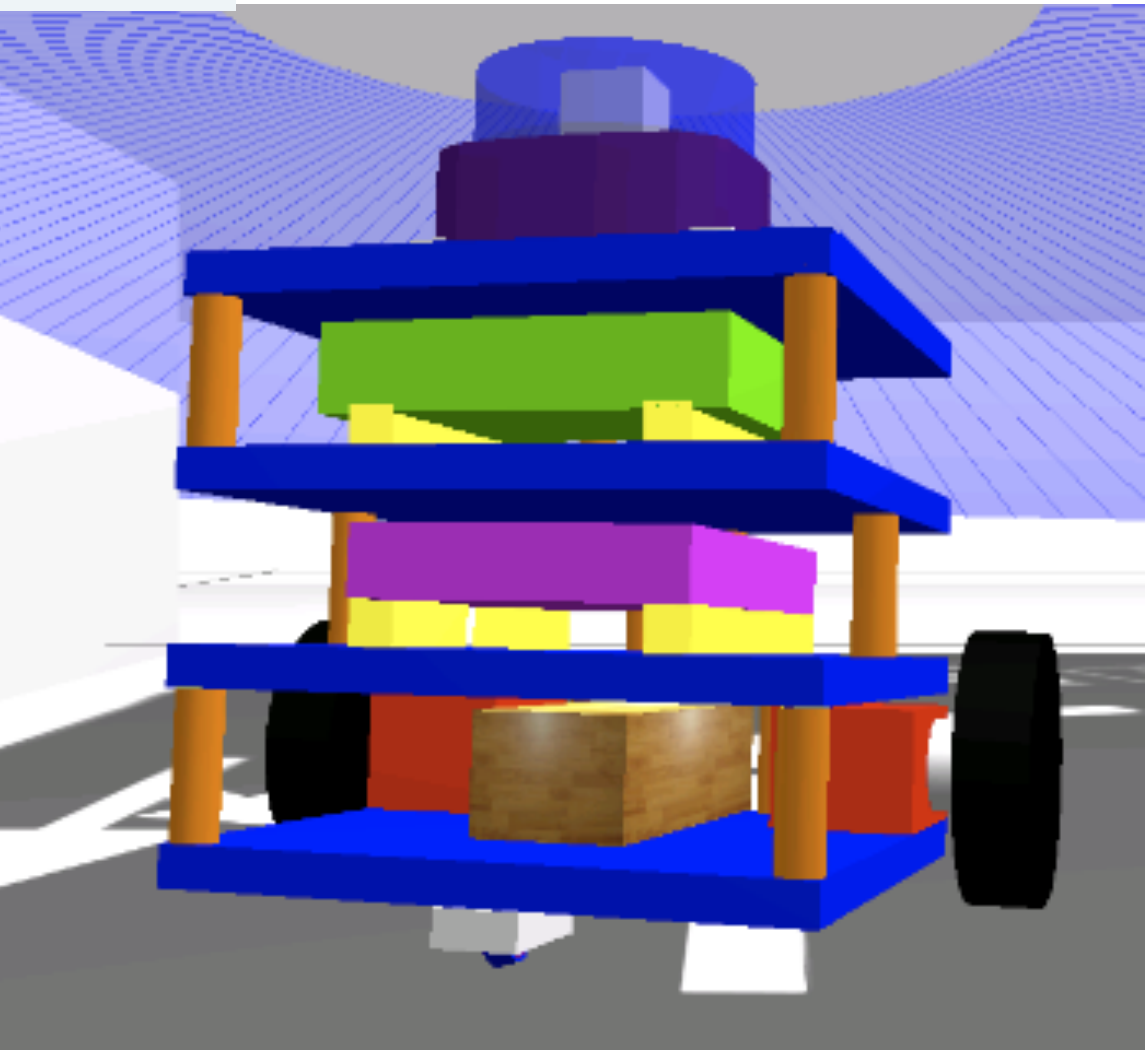
- Final model in RVIZ2 and Gazebo along with demo on simulator



RViz2



Gazebo

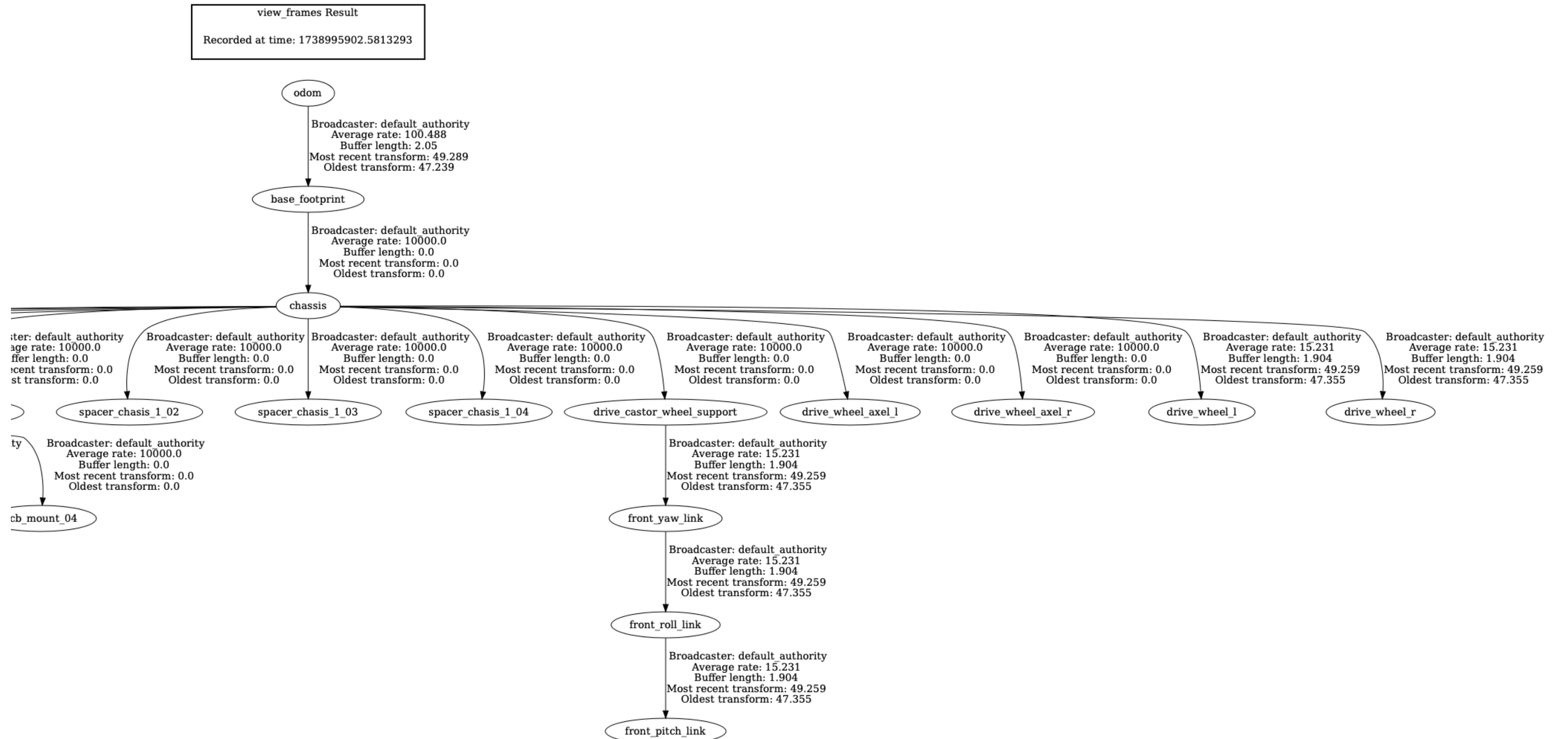


Next : Demo on real robot

URDF

Micro Project

- TF tree

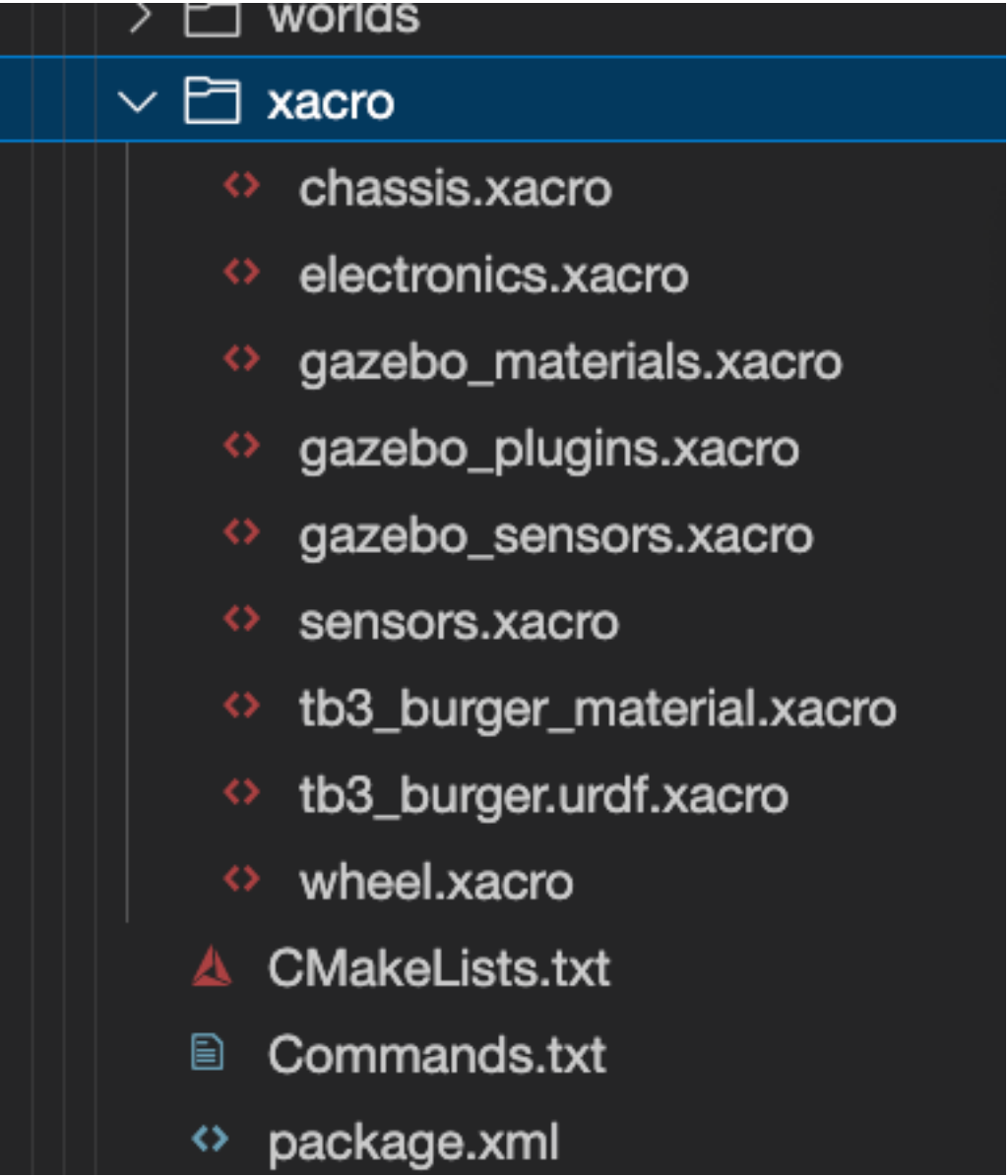
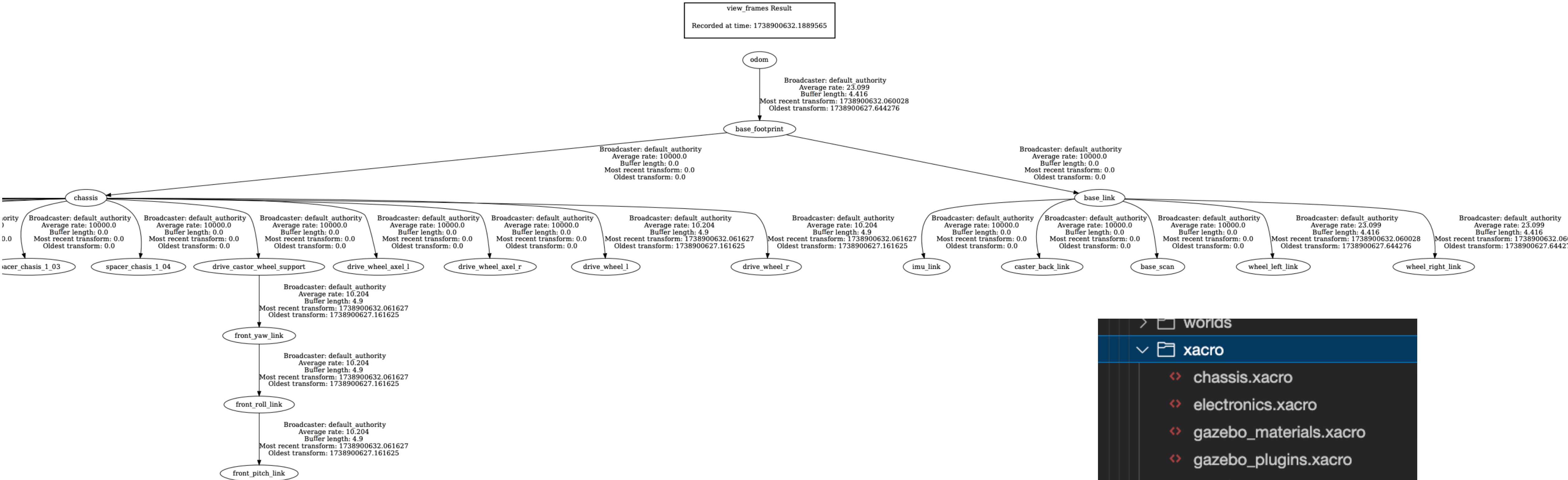


Full image = tf_tree.pdf

URDF

Micro Project

- Merged TF tree



Full image image = [merged.pdf](#)

Thank you !