

Industrial Robotics

Introduction to ROS

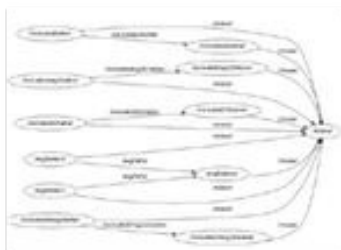
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Overview

- ROS architecture & philosophy
- ROS master, nodes, and topics
- Console commands
- Catkin workspace and build system
- Launch-files
- Gazebo simulator

What is ROS?

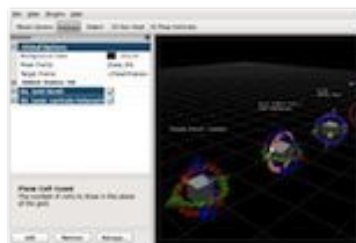
ROS = Robot Operating System



Plumbing

- Process management
- Inter-process communication
- Device drivers

+



Tools

- Simulation
- Visualization
- Graphical user interface
- Data logging

+



Capabilities

- Control
- Planning
- Perception
- Mapping
- Manipulation

+



Ecosystem

- Package organization
- Software distribution
- Documentation
- Tutorials

ros.org

History of ROS

- Originally developed in 2007 at the Stanford Artificial Intelligence Laboratory
- Since 2013 managed by OSRF
- Today used by many robots, universities and companies
- De facto standard for robot programming



ros.org

ROS Philosophy

- **Peer to peer**
Individual programs communicate over defined API (ROS *messages*, *services*, etc.).
- **Distributed**
Programs can be run on multiple computers and communicate over the network.
- **Multi-lingual**
ROS modules can be written in any language for which a client library exists (C++, Python, MATLAB, Java, etc.).
- **Light-weight**
Stand-alone libraries are wrapped around with a thin ROS layer.
- **Free and open-source**
Most ROS software is open-source and free to use.

ROS Master

- Manages the communication between nodes (processes)
- Every node registers at startup with the master

ROS Master

Start a master with

```
> roscore
```

More info

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

ROS Nodes

- Single-purpose, executable program
- Individually compiled, executed, and managed
- Organized in *packages*

Run a node with

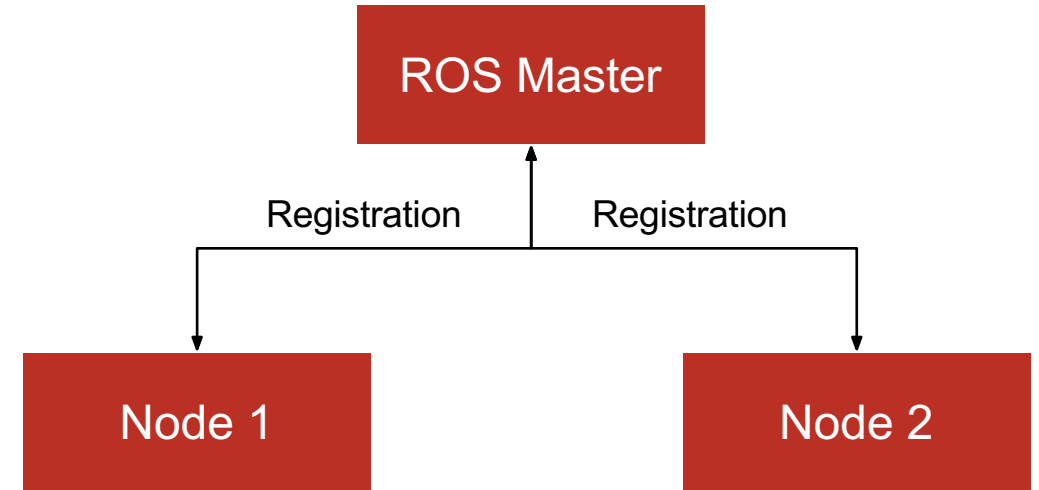
```
> rosrun package_name node_name
```

See active nodes with

```
> rosnodetop
```

Retrieve information about a node with

```
> rosnodetop node_name
```



More info

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

ROS Topics

- Nodes communicate over *topics*
 - Nodes can *publish* or *subscribe* to a topic
 - Typically, 1 publisher and *n* subscribers
- Topic is a name for a stream of *messages*

List active topics with

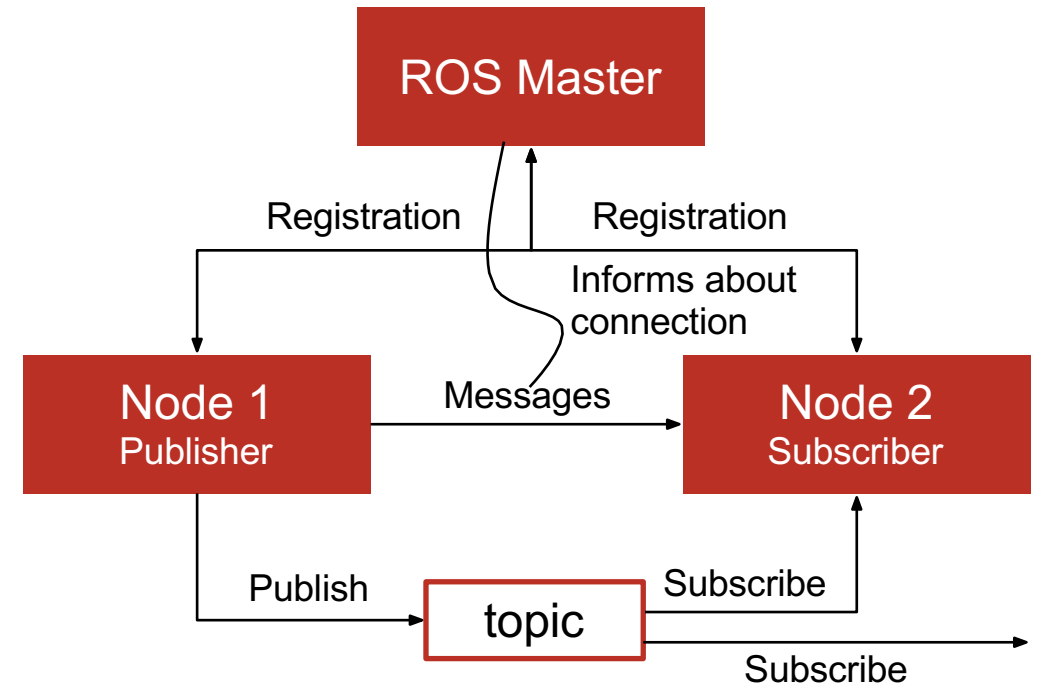
```
> rostopic list
```

Subscribe and print the contents of a topic with

```
> rostopic echo /topic
```

Show information about a topic with

```
> rostopic info /topic
```



More info

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

ROS Messages

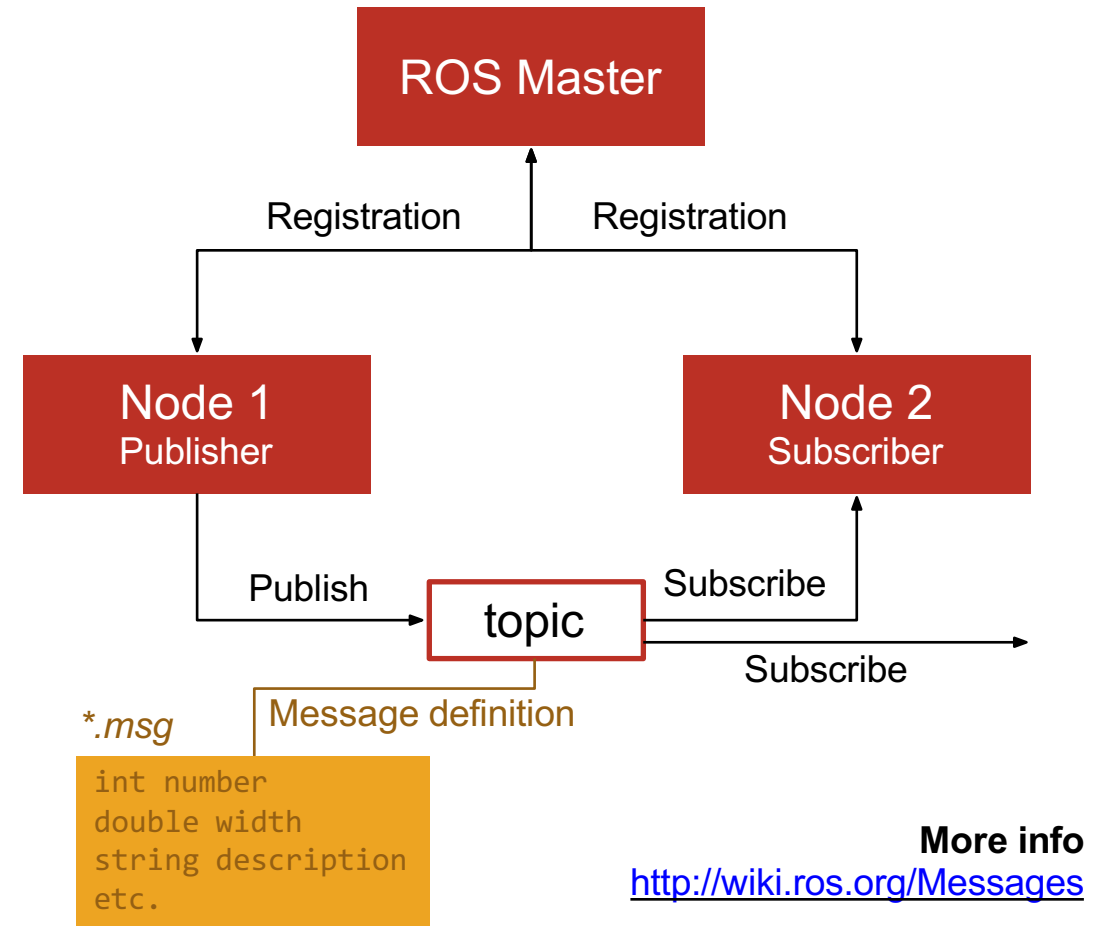
- Data structure defining the *type* of a topic
- Comprised of a nested structure of integers, floats, booleans, strings etc. and arrays of objects
- Defined in **.msg* files

See the type of a topic

```
> rostopic type /topic
```

Publish a message to a topic

```
> rostopic pub /topic type data
```



ROS Messages

Pose Stamped Example

[geometry_msgs/Point.msg](#)

```
float64 x
float64 y
float64 z
```

[sensor_msgs/Image.msg](#)

```
std_msgs/Header header
  uint32 seq
  time stamp
  string frame_id
uint32 height
uint32 width
string encoding
uint8 is_bigendian
uint32 step
uint8[] data
```

[geometry_msgs/PoseStamped.msg](#)

```
std_msgs/Header header
uint32 seq
time stamp
string frame_id
geometry_msgs/Pose pose
  geometry_msgs/Point position
    float64 x
    float64 y
    float64 z
  geometry_msgs/Quaternion orientation
    float64 x
    float64 y
    float64 z
    float64 w
```

Example

Console Tab Nr. 1 – Starting a *roscore*

Start a roscore with

```
> roscore
```

```
student@ubuntu:~/catkin_ws$ roscore
... logging to /home/student/.ros/log/6c1852aa-e961-11e6-8543-000c297bd368/ros
launch-ubuntu-6696.log
Checking log directory for disk usage. This may take awhile.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://ubuntu:34089/
ros_comm version 1.11.20

SUMMARY
=====

PARAMETERS
* /rostdistro: indigo
* /rosversion: 1.11.20

NODES

auto-starting new master
process[master]: started with pid [6708]
ROS_MASTER_URI=http://ubuntu:11311/

setting /run_id to 6c1852aa-e961-11e6-8543-000c297bd368
process[rosout-1]: started with pid [6721]
started core service [/rosout]
```

Example

Console Tab Nr. 2 – Starting a *talker* node

Run a talker demo node with

```
> rosrun roscpp_tutorials talker
```

```
student@ubuntu:~/catkin_ws$ rosrun roscpp_tutorials talker
[ INFO] [1486051708.424661519]: hello world 0
[ INFO] [1486051708.525227845]: hello world 1
[ INFO] [1486051708.624747612]: hello world 2
[ INFO] [1486051708.724826782]: hello world 3
[ INFO] [1486051708.825928577]: hello world 4
[ INFO] [1486051708.925379775]: hello world 5
[ INFO] [1486051709.024971132]: hello world 6
[ INFO] [1486051709.125450960]: hello world 7
[ INFO] [1486051709.225272747]: hello world 8
[ INFO] [1486051709.325389210]: hello world 9
```

Example

Console Tab Nr. 3 – Analyze *talker* node

See the list of active nodes

```
> roscd list
```

```
student@ubuntu:~/catkin_ws$ roscd list
/rosout
/talker
```



Show information about the *talker* node

```
> roscd info /talker
```

```
student@ubuntu:~/catkin_ws$ roscd info /talker
-----
--
Node [/talker]
Publications:
 * /chatter [std_msgs/String]
 * /rosout [roscpp_msgs/Log]
Subscriptions: None
Services:
 * /talker/get_loggers
 * /talker/set_logger_level
```



See information about the *chatter* topic

```
> rostopic info /chatter
```

```
student@ubuntu:~/catkin_ws$ rostopic info /chatter
Type: std_msgs/String

Publishers:
 * /talker (http://ubuntu:39173/)
Subscribers: None
```



Example

Console Tab Nr. 3 – Analyze *chatter* topic

Check the type of the *chatter* topic

```
> rostopic type /chatter
```

```
student@ubuntu:~/catkin_ws$ rostopic type /chatter  
std_msgs/String
```

Show the message contents of the topic

```
> rostopic echo /chatter
```

```
student@ubuntu:~/catkin_ws$ rostopic echo /chatter  
data: hello world 11874  
---  
data: hello world 11875  
---  
data: hello world 11876
```

Analyze the frequency

```
> rostopic hz /chatter
```

```
student@ubuntu:~/catkin_ws$ rostopic hz /chatter  
subscribed to [/chatter]  
average rate: 9.991  
  min: 0.099s max: 0.101s std dev: 0.00076s window: 10  
average rate: 9.996  
  min: 0.099s max: 0.101s std dev: 0.00069s window: 20
```

Example

Console Tab Nr. 4 – Starting a *listener* node

Run a listener demo node with

```
> rosrunc roscpp_tutorials listener
```

```
student@ubuntu:~/catkin_ws$ rosrunc roscpp_tutorials listener
[ INFO] [1486053802.204104598]: I heard: [hello world 19548]
[ INFO] [1486053802.304538827]: I heard: [hello world 19549]
[ INFO] [1486053802.403853395]: I heard: [hello world 19550]
[ INFO] [1486053802.504438133]: I heard: [hello world 19551]
[ INFO] [1486053802.604297608]: I heard: [hello world 19552]
```

Example

Console Tab Nr. 3 – Analyze

See the new *listener* node with

```
> rosnod list
```

```
student@ubuntu:~/catkin_ws$ rosnod list
/listener
/rosout
/talker
```

Show the connection of the nodes over the chatter topic with

```
> rostopic info /chatter
```

```
student@ubuntu:~/catkin_ws$ rostopic info /chatter
Type: std_msgs/String

Publishers:
* /talker (http://ubuntu:39173/)

Subscribers:
* /listener (http://ubuntu:34664/)
```


Example

Console Tab Nr. 3 – Publish Message from Console

Close the *talker* node in console nr. 2 with Ctrl + C

Publish your own message with

```
> rostopic pub /chatter std_msgs/String  
"data: 'ROS Course'"
```

```
student@ubuntu:~/catkin_ws$ rostopic pub /chatter std_msgs/String "data: 'ETH  
Zurich ROS Course'"  
publishing and latching message. Press ctrl-C to terminate
```

Check the output of the *listener* in console nr. 4

ROS Workspace Environment

- Defines context for the current workspace
- Default workspace loaded with

```
> source /opt/ros/noetic/setup.bash
```

Overlay your *catkin* workspace with

```
> cd ~/catkin_ws  
> source devel/setup.bash
```

Check your workspace with

```
> echo $ROS_PACKAGE_PATH
```

This is
already
setup in the
provided
installation.

See setup with

```
> cat ~/.bashrc
```

More info

<http://wiki.ros.org/kinetic/Installation/Ubuntu>

<http://wiki.ros.org/catkin/workspaces>

catkin Build System

- *catkin* is the ROS build system to generate executables, libraries, and interfaces
- We suggest to use the *Catkin Command Line Tools*

→ Use `catkin build` instead of `catkin_make`

Navigate to your catkin workspace with

```
> cd ~/catkin_ws
```

Build a package with

```
> catkin build package_name
```

! Whenever you build a **new** package, update your environment

```
> source devel/setup.bash
```

The catkin
command line
tools are
pre-installed in
the provided
installation.

More info

<http://wiki.ros.org/catkin/Tutorials>

<https://catkin-tools.readthedocs.io/>

catkin Tools Quick Start

Initialization of a workspace can be done automatically with catkin build

- Creating a new workspace with an empty **source space** (named **src** by default)
- Calling catkin init from the workspace root:

```
source /opt/ros/noetic/setup.bash      # Source ROS noetic to use Catkin
mkdir -p /tmp/quickstart_ws/src        # Make a new workspace and source space
cd /tmp/quickstart_ws                  # Navigate to the workspace root
catkin init                            # Initialize it with a hidden marker file
```

<https://catkin-tools.readthedocs.io/en/latest/installing.html>

catkin Build System

The catkin workspace contains the following spaces

Work here



src

The *source space* contains the source code. This is where you can clone, create, and edit source code for the packages you want to build.

Don't touch



build

The *build space* is where CMake is invoked to build the packages in the source space. Cache information and other intermediate files are kept here.

Don't touch



devel

The *development (devel) space* is where built targets are placed (prior to being installed).

If necessary, clean the entire build and devel space with

```
> catkin clean
```

More info

<http://wiki.ros.org/catkin/workspaces>

ROS Launch

- *launch* is a tool for launching multiple nodes (as well as setting parameters)
- Are written in XML as **.launch* files
- If not yet running, launch automatically starts a roscore

Browse to the folder and start a launch file with

```
> roslaunch file_name.launch
```

Start a launch file from a package with

```
> roslaunch package_name file_name.launch
```

More info

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

Example console output for
roslaunch roscpp_tutorials talker_listener.launch

```
student@ubuntu:~/catkin_ws$ roslaunch roscpp_tutorials talker_listener.launch
... logging to /home/student/.ros/log/794321aa-e950-11e6-95db-000c297bd368/rosl
Checking log directory for disk usage. This may take awhile.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://ubuntu:37592/

SUMMARY
=====

PARAMETERS
* /rostdistro: indigo
* /rosversion: 1.11.20

NODES
/
  listener (roscpp_tutorials/listener)
  talker (roscpp_tutorials/talker)

auto-starting new master
process[master]: started with pid [5772]
ROS_MASTER_URI=http://localhost:11311

setting /run_id to 794321aa-e950-11e6-95db-000c297bd368
process[rosout-1]: started with pid [5785]
started core service [/rosout]
process[listener-2]: started with pid [5788]
process[talker-3]: started with pid [5795]
[ INFO] [1486044252.537801350]: hello world 0
[ INFO] [1486044252.638886504]: hello world 1
[ INFO] [1486044252.738279674]: hello world 2
[ INFO] [1486044252.838357245]: hello world 3
```

ROS Launch File Structure

! Attention when copy & pasting code from the internet

[talker_listener.launch](#)

```
<launch>  
  <node name="listener" pkg="roscpp_tutorials" type="listener" output="screen"/>  
  <node name="talker" pkg="roscpp_tutorials" type="talker" output="screen"/>  
</launch>
```

! Notice the syntax difference
for self-closing tags:
<tag></tag> and <tag/>

- **launch:** Root element of the launch file
- **node:** Each `<node>` tag specifies a node to be launched
- **name:** Name of the node (free to choose)
- **pkg:** Package containing the node
- **type:** Type of the node, there must be a corresponding executable with the same name
- **output:** Specifies where to output log messages (screen: console, log: log file)

More info

<http://wiki.ros.org/roslaunch/XML>

<http://wiki.ros.org/roslaunch/Tutorials/Roslaunch%20tips%20for%20larger%20projects>

ROS Launch Arguments

- Create re-usable launch files with `<arg>` tag, which works like a parameter (default optional)

```
<arg name="arg_name" default="default_value"/>
```

- Use arguments in launch file with

```
$(arg arg_name)
```

- When launching, arguments can be set with

```
> roslaunch launch_file.launch arg_name:=value
```

[range_world.launch](#) (simplified)

```
<?xml version="1.0"?>
<launch>
  <arg name="use_sim_time" default="true"/>
  <arg name="world" default="gazebo_ros_range"/>
  <arg name="debug" default="false"/>
  <arg name="physics" default="ode"/>

  <group if="$(arg use_sim_time)">
    <param name="/use_sim_time" value="true" />
  </group>

  <include file="$(find gazebo_ros)
                                     /launch/empty_world.launch">
    <arg name="world_name" value="$(find gazebo_plugins)/
                                     test/test_worlds/$(arg world).world"/>
    <arg name="debug" value="$(arg debug)"/>
    <arg name="physics" value="$(arg physics)"/>
  </include>
</launch>
```

More info

<http://wiki.ros.org/roslaunch/XML/arg>

ROS Launch

Including Other Launch Files

- Include other launch files with `<include>` tag to organize large projects

```
<include file="package_name"/>
```

- Find the system path to other packages with

```
$(find package_name)
```

- Pass arguments to the included file

```
<arg name="arg_name" value="value"/>
```

[range_world.launch](#) (simplified)

```
<?xml version="1.0"?>
<launch>
  <arg name="use_sim_time" default="true"/>
  <arg name="world" default="gazebo_ros_range"/>
  <arg name="debug" default="false"/>
  <arg name="physics" default="ode"/>

  <group if="$(arg use_sim_time)">
    <param name="/use_sim_time" value="true" />
  </group>

  <include file="$(find gazebo_ros)
                                     /launch/empty_world.launch">
    <arg name="world_name" value="$(find gazebo_plugins)/
                                     test/test_worlds/$(arg world).world"/>
    <arg name="debug" value="$(arg debug)"/>
    <arg name="physics" value="$(arg physics)"/>
  </include>
</launch>
```

More info

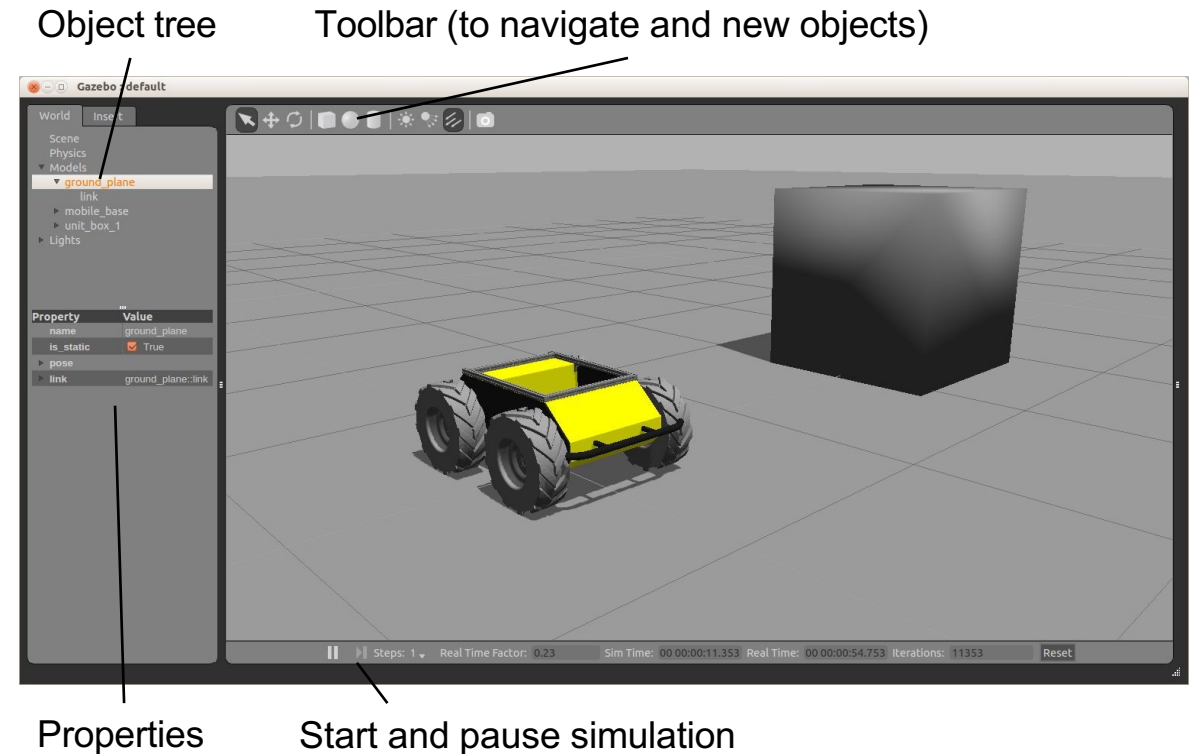
<http://wiki.ros.org/roslaunch/XML/include>

Gazebo Simulator

- Simulate 3d rigid-body dynamics
- Simulate a variety of sensors including noise
- 3d visualization and user interaction
- Includes a database of many robots and environments (*Gazebo worlds*)
- Provides a ROS interface
- Extensible with plugins

Run Gazebo with

```
> rosrunc gazebo_ros gazebo
```



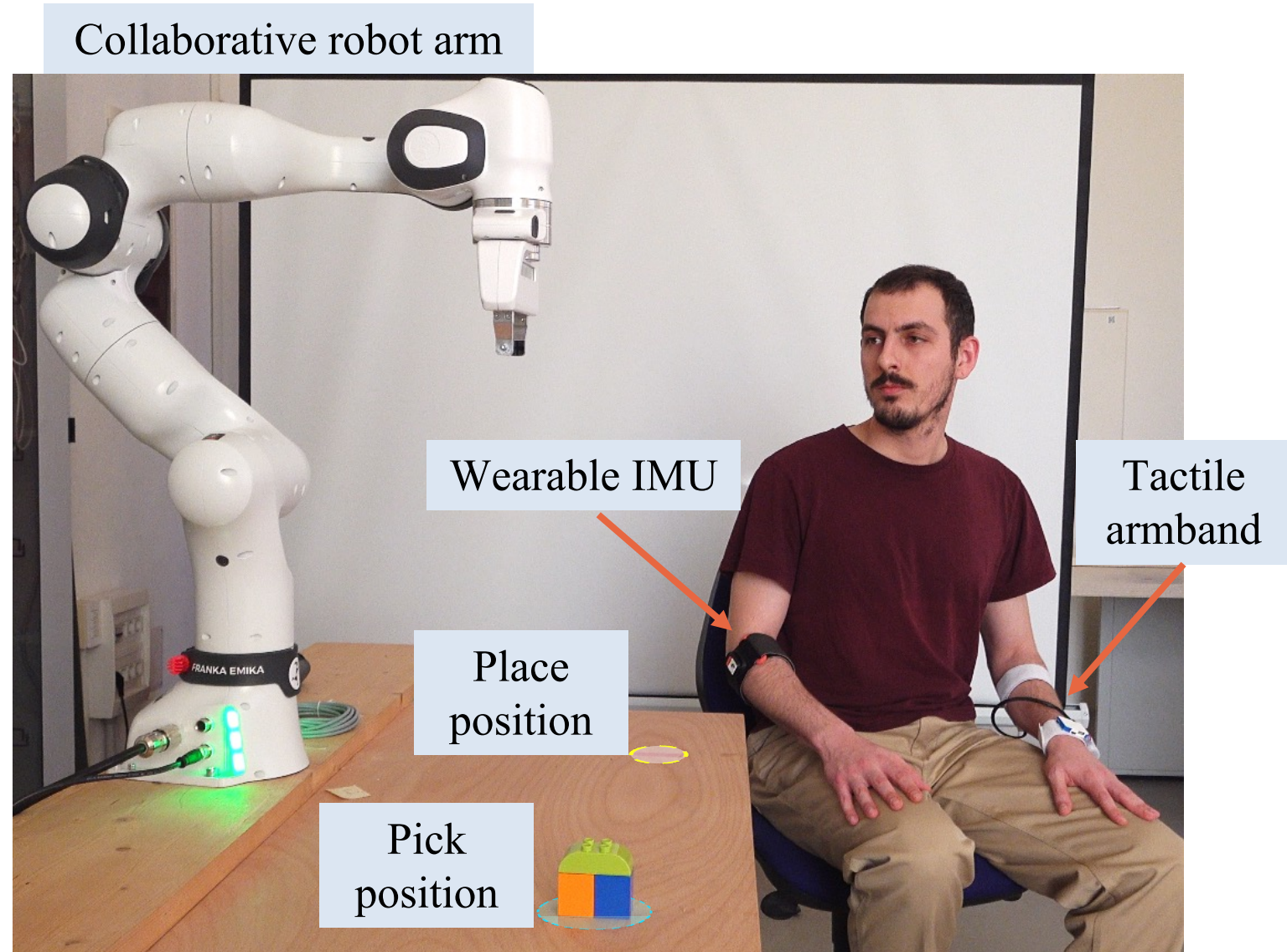
More info

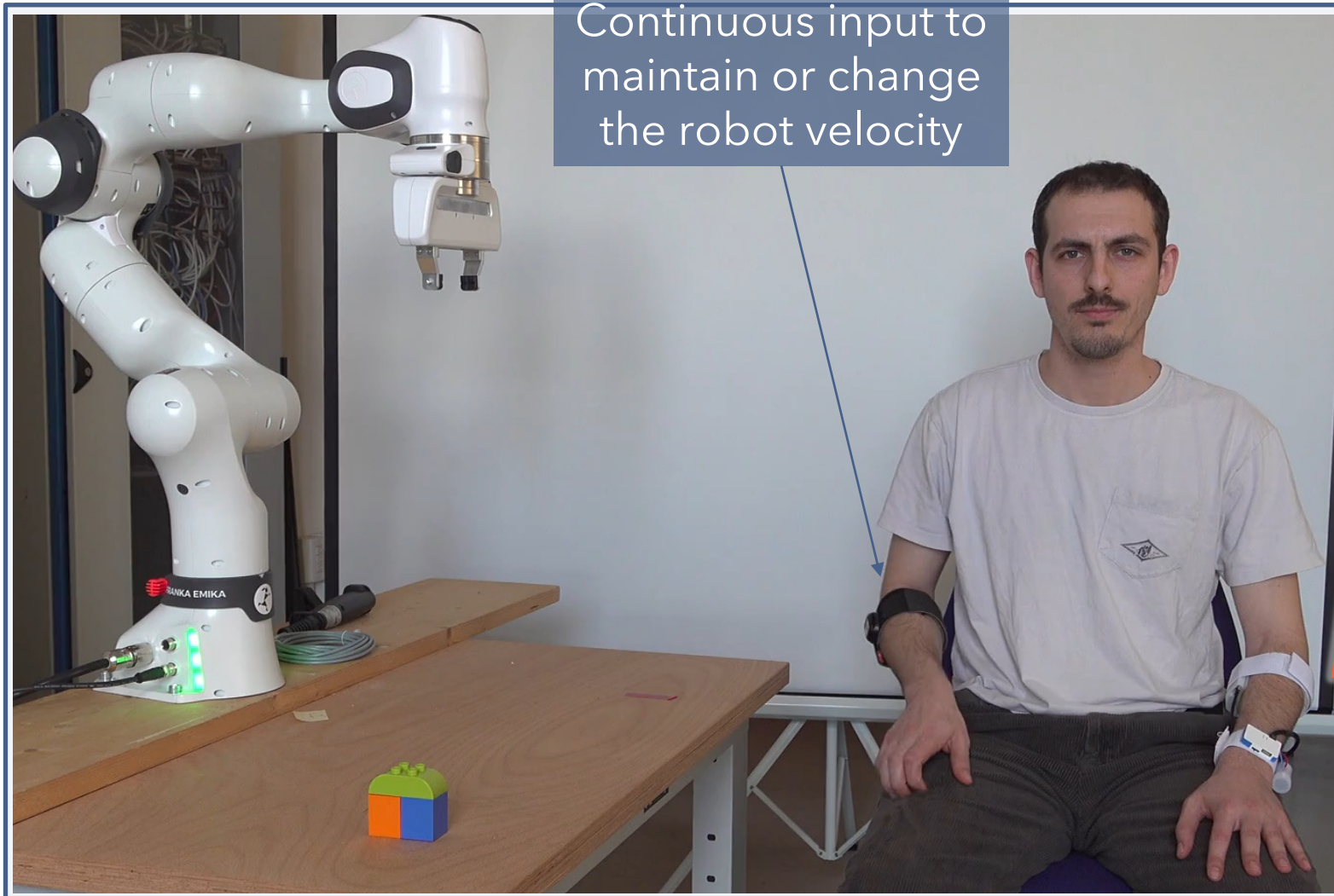
<http://gazebosim.org/>

<http://gazebosim.org/tutorials>

Example

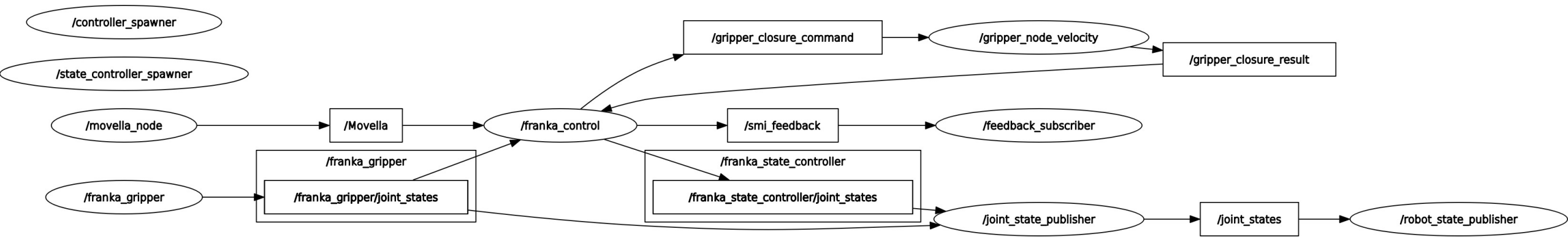
Pick and place task





Continuous vibration while the robot is moving and continuous skin indentation while the robot is holding the object

ROS Graph



Further References

- **ROS Wiki**
 - <http://wiki.ros.org/>
- **Installation**
 - <http://wiki.ros.org/ROS/Installation>
- **Tutorials**
 - <http://wiki.ros.org/ROS/Tutorials>
- **Available packages**
 - <http://www.ros.org/browse/>
- **ROS Cheat Sheet**
 - <https://www.clearpathrobotics.com/ros-robot-operating-system-cheat-sheet/>
 - https://kapeli.com/cheat_sheets/ROS.docset/Contents/Resources/Documents/index
- **ROS Best Practices**
 - https://github.com/leggedrobotics/ros_best_practices/wiki
- **ROS Package Template**
 - https://github.com/leggedrobotics/ros_best_practices/tree/master/ros_package_template