



Programming for Robotics

Introduction to ROS

Course 1

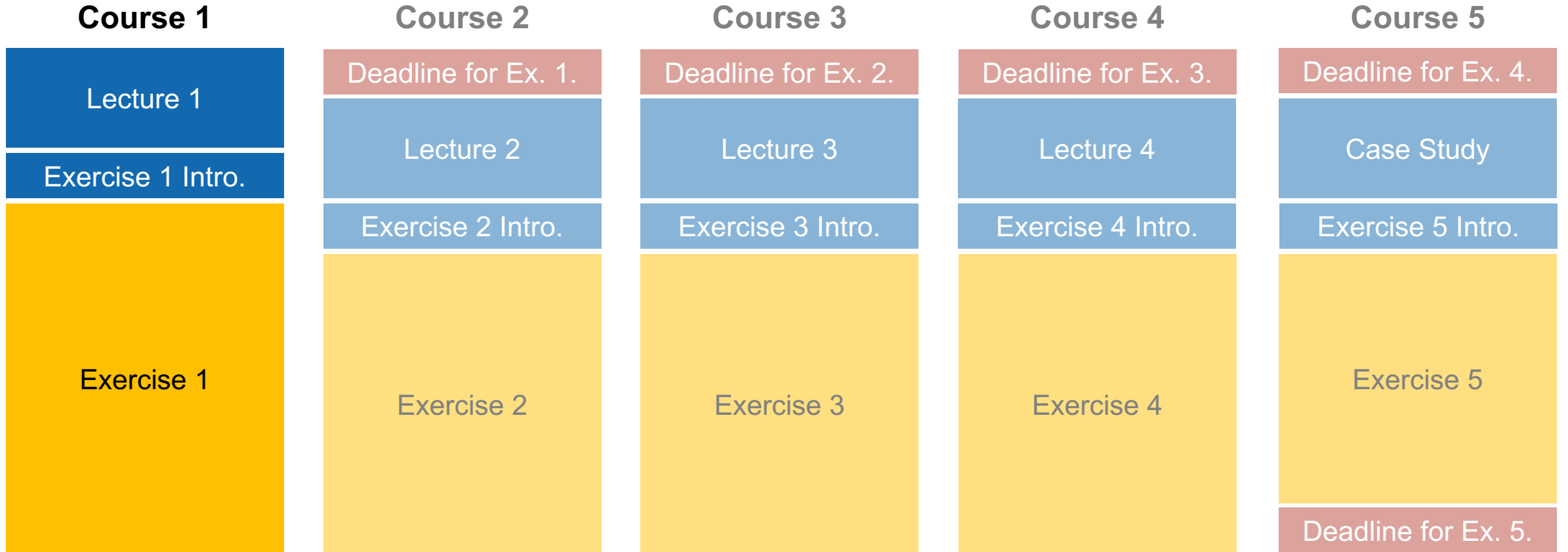
Péter Fankhauser, Dominic Jud, Martin Wermelinger
Prof. Dr. Marco Hutter



Overview

- **Course 1**
 - ROS architecture & philosophy
 - ROS master, nodes, and topics
 - Console commands
 - Catkin workspace and build system
 - Launch-files
 - Gazebo simulator
- **Course 2**
 - ROS package structure
 - Integration and programming with Eclipse
 - ROS C++ client library (roscpp)
 - ROS subscribers and publishers
 - ROS parameter server
 - RViz visualization
- **Course 3**
 - TF Transformation System
 - rqt User Interface
 - Robot models (URDF)
 - Simulation descriptions (SDF)
- **Course 4**
 - ROS services
 - ROS actions (actionlib)
 - ROS time
 - ROS bags
- **Course 5**
 - Case study

Course Structure



Exercise Evaluation

- Each exercise has several check questions
- Each exercise counts for 20% of the final grade
- We encourage team work, but every student has to show the results on his own PC and is evaluated individually
- Exercises are checked by the teaching assistants when you are reading, but latest the following course day in the morning (08:15–08:45, except for exercise 5)
- Let the teaching assistant know once you are reading to present your results
- **The lectures start at 08:45**

Overview Course 1

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

What is ROS?

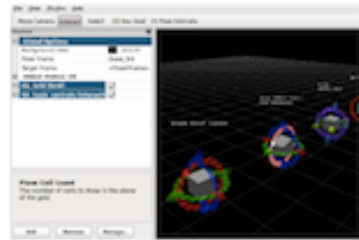
ROS = Robot Operating System



Plumbing

- Process management
- Inter-process communication
- Device drivers

+



Tools

- Simulation
- Visualization
- Graphical user interface
- Data logging

+



Capabilities

- Control
- Planning
- Perception
- Mapping
- Manipulation

+



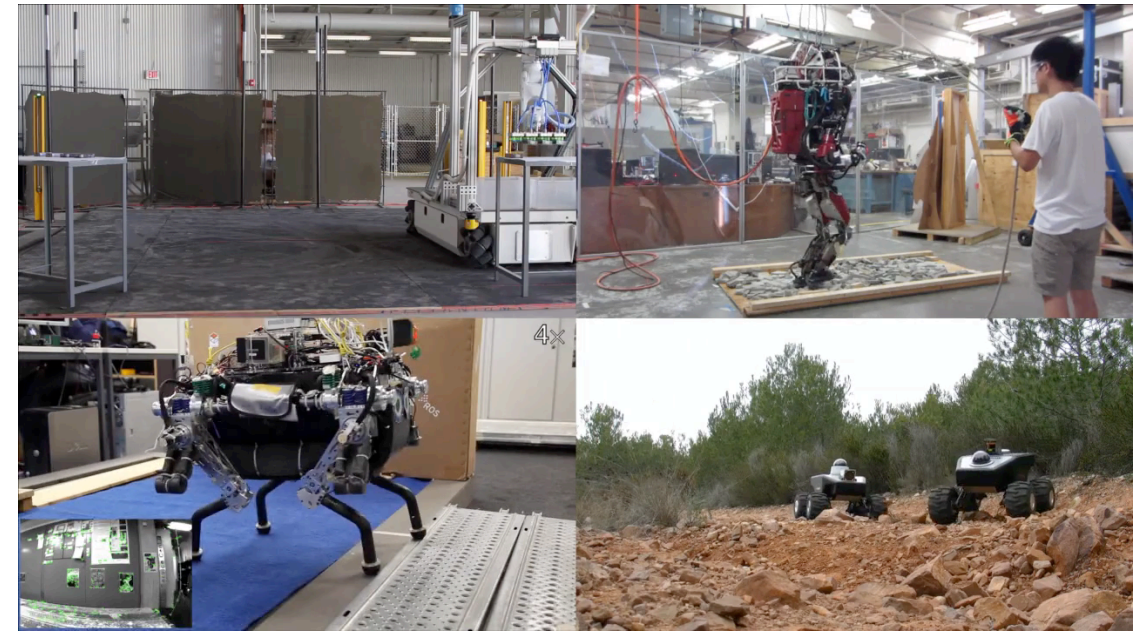
ros.org

Ecosystem

- Package organization
- Software distribution
- Documentation
- Tutorials

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 Workspace Environment

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


```
> source /opt/ros/indigo/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/indigo/Installation/Ubuntu>

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

ROS Master

- Manages the communication between nodes
- 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

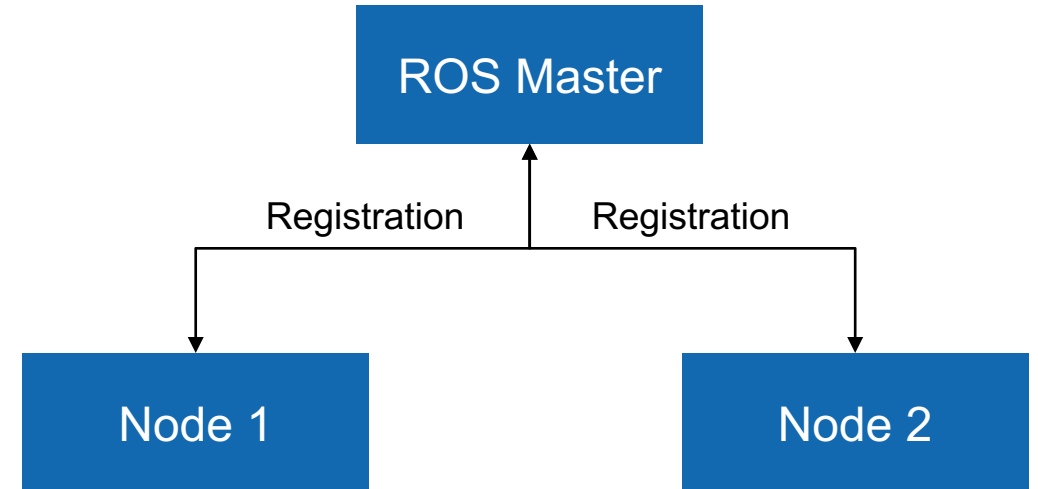
```
> rosrun package_name node_name
```

See active nodes with

```
> rosnode list
```

Retrieve information about a node with

```
> rosnode info 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

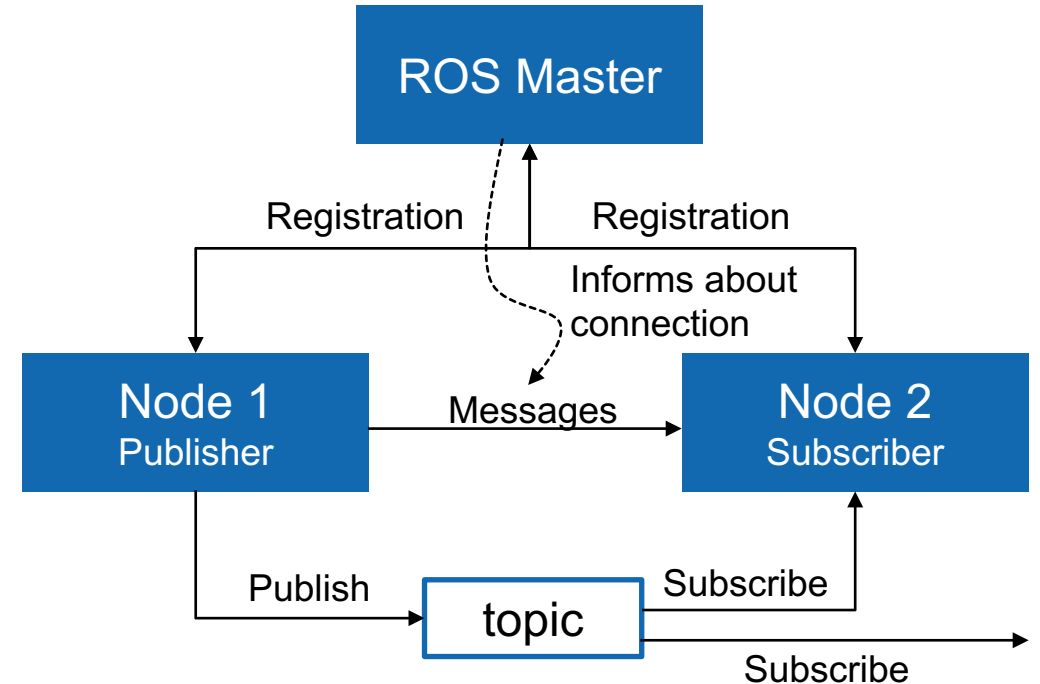
```
> rostopic list
```

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

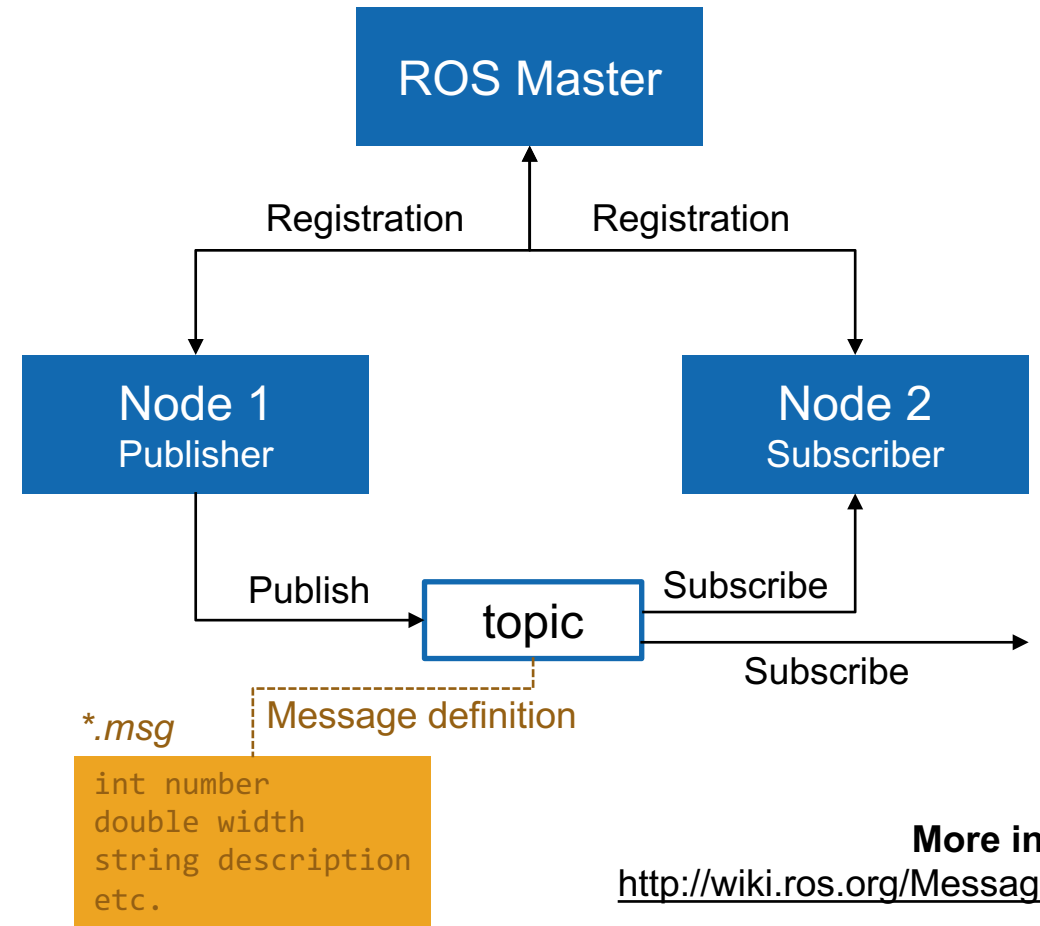
- Data structure defining the *type* of a topic
- Comprised of a nested structure of integers, floats, booleans, strings etc. and arrays of objects
- Defined in **.msg* files

See the type of a topic

```
> rostopic type /topic
```

Publish a message to a topic

```
> rostopic pub /topic type args
```



More info

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

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

```
> rosnode list
```


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



Show information about the *talker* node

```
> rosnode info /talker
```



```
student@ubuntu:~/catkin_ws$ rosnode info /talker
-----
--
Node [/talker]
Publications:
 * /chatter [std_msgs/String]
 * /rosout [rosgraph_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

```
> rosnode list
```

```
student@ubuntu:~/catkin_ws$ rosnode 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: 'ETH Zurich 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

```
[ INFO ] [1486054667.56418772]: I heard: [hello world 28201]  
[ INFO ] [1486054667.604322265]: I heard: [hello world 28202]  
[ INFO ] [1486054667.704264199]: I heard: [hello world 28203]  
[ INFO ] [1486054667.804389058]: I heard: [hello world 28204]  
[ INFO ] [1486054707.646404558]: I heard: [ETH Zurich ROS Course]
```



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 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>

catkin Build System

The catkin workspace setup can be checked with

```
> catkin config
```

For example, to set the *CMake build type* to Release (or Debug etc.), use

```
> catkin build --cmake-args
    -DCMAKE_BUILD_TYPE=Release
```

More info

http://catkin-tools.readthedocs.io/en/latest/verbs/catkin_config.html

http://catkin-tools.readthedocs.io/en/latest/cheat_sheet.html

```
student@ubuntu:~/catkin_ws$ catkin config
-----
Profile:                default
Extending:              [env] /opt/ros/indigo:/home/student/catkin_ws/devel
Workspace:              /home/student/catkin_ws
-----
Source Space:          [exists] /home/student/catkin_ws/src
Log Space:             [exists] /home/student/catkin_ws/logs
Build Space:           [exists] /home/student/catkin_ws/build
Devel Space:           [exists] /home/student/catkin_ws/devel
Install Space:         [unused] /home/student/catkin_ws/install
DESTDIR:               [unused] None
-----
Devel Space Layout:    linked
Install Space Layout:  None
-----
Additional CMake Args: -GEclipse CDT4 - Unix Makefiles -DCMAKE_CXX_COMP
ILER_ARG1=-std=c++11 -DCMAKE_BUILD_TYPE=Release
Additional Make Args:  None
Additional catkin Make Args: None
Internal Make Job Server: True
Cache Job Environments: False
-----
Whitelisted Packages: None
Blacklisted Packages: None
-----
Workspace configuration appears valid.
```

Already
setup in the
provided
installation.

Example

Open a terminal and browse to your git folder

```
> cd ~/git
```

Clone the Git repository with

```
> git clone https://github.com/ethz-  
asl/ros_best_practices.git
```

Symlink the new package to your catkin workspace

```
> ln -s ~/git/ros_best_practices/ ~/catkin_ws/src/
```

Note: You could also directly clone to your catkin workspace, but using a common git folder is convenient if you have multiple catkin workspaces.

https://github.com/ethz-asl/ros_best_practices

1 contributor BSD-3-Clause

Create new file Upload files Find file Clone or download ▾

Clone with HTTPS ⓘ Use SSH

Use Git or checkout with SVN using the web URL.

https://github.com/ethz-asl/ros_best_practices 📄

Open in Desktop Download ZIP

2 years ago

Example

Go to your catkin workspace

```
> cd ~/catkin_ws
```

Build the package with

```
> catkin build ros_package_template
```

Re-source your workspace setup

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

Launch the node with

```
> roslaunch ros_package_template
  ros_package_template.launch
```

```
NOTE: Forcing CMake to run for each package.
-----
[build] Found '1' packages in 0.0 seconds.
[build] Updating package table.
Starting >>> catkin_tools_prebuild
Finished <<< catkin_tools_prebuild [ 1.0 seconds ]
Starting >>> ros_package_template
Finished <<< ros_package_template [ 4.1 seconds ]
[build] Summary: All 2 packages succeeded!
[build] Ignored: None.
[build] Warnings: None.
[build] Abandoned: None.
[build] Failed: None.
[build] Runtime: 5.2 seconds total.
[build] Note: Workspace packages have changed, please re-source setup files to use them.
student@ubuntu:~/catkin_ws$
```

```
  /ros_package_template/subscriber_topic: /temperature
* /roscolor: indigo
* /rosversion: 1.11.20

NODES
/
  ros_package_template (ros_package_template/ros_package_template)

auto-starting new master
process[master]: started with pid [27185]
ROS_MASTER_URI=http://localhost:11311

setting /run_id to e43f937a-ed52-11e6-9789-000c297bd368
process[rosout-1]: started with pid [27198]
started core service [/rosout]
process[ros_package_template-2]: started with pid [27201]
[ INFO] [1486485095.843512614]: Successfully launched node.
```

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/ros1
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

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

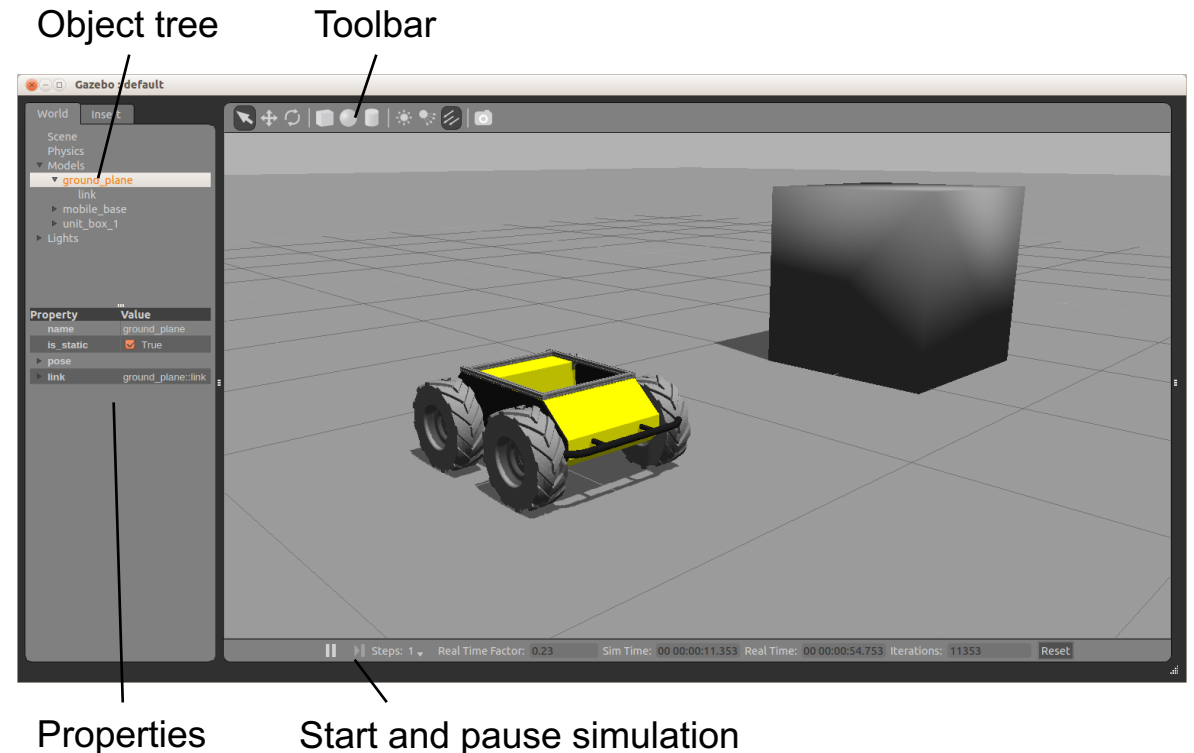
<http://wiki.ros.org/roslaunch/XML/include>

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>

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://github.com/ros/cheatsheet/releases/download/0.0.1/ROSCheatsheet_catkin.pdf
- **ROS Best Practices**
 - https://github.com/ethz-asl/ros_best_practices/wiki
- **ROS Package Template**
 - https://github.com/ethz-asl/ros_best_practices/tree/master/ros_package_template

Contact Information

ETH Zurich

Robotic Systems Lab
Prof. Dr. Marco Hutter
LEE J 225
Leonhardstrasse 21
8092 Zurich
Switzerland

<http://www.rsl.ethz.ch>

Lecturers

Péter Fankhauser (pfankhauser@ethz.ch)
Dominic Jud
Martin Wermelinger

Course website:

<http://www.rsl.ethz.ch/education-students/lectures/ros.html>