Table of Contents

Preface	χi
Chapter 1: Getting Started with ROS	1
What does ROS do and what are the benefits of learning ROS?	2
Who controls ROS?	3
Which robots are using ROS?	3
Installing and launching ROS	5
Configuring your Ubuntu repositories	6
Setting up your sources.list file	6
Setting up your keys	7
Installing ROS Kinetic	7
Initialize rosdep	7
Environment setup	8
Getting rosinstall	8
Troubleshooting – examining your ROS environment	8
Creating a catkin workspace	9
ROS packages and manifest	10
ROS manifest	11
Exploring the ROS packages	11
rospack find packages	12
rospack list	12 13
ROS nodes, topics, and messages	14
ROS nodes	14
ROS topics	15
ROS messages	
ROS Master Invoking the ROS Master using roscore	15 16
ROS commands to determine the nodes and topics	17
1,00 commands to determine the hodes and topios	



Turtlesim – the first ROS robot simulation Starting turtlesim nodes rosrun command Turtlesim nodes Turtlesim topics and messages rostopic list rostopic type rosmsg list rosmsg show rostopic echo Move the turtle by publishing /turtle1/cmd_vel Move the turtle using the keyboard or joystick Parameter Server of Turtlesim rosparam help rosparam list for the /turtlesim node Change parameters for the color of the turtle's background ROS services to move turtle rosservice call ROS commands summary Summary	19 19 20 21 23 24 24 24 25 25 26 28 28 29 29 30 31 32
Chapter 2: Creating Your First Two-Wheeled ROS Robot (in Simulation)	
	35
Introducing rviz	36
Installing and launching rviz Getting familiar with rviz	36
Displays panel	38
Views and Time panels	38 39
Toolbar	40
Main window menu bar	41
Creating and building a ROS package	41
Building a differential drive robot URDF	42
Creating a robot chassis	43
Using roslaunch	44
Adding wheels	48
Adding a caster	51
Adding color	52
Adding collisions	54
Moving the wheels	55
A word about tf and robot_state_publisher	57
Adding physical properties	57
Trying URDF tools	59
check_urdf	59
urdf_to_graphiz	59

Gazebo	60
Installing and launching Gazebo	61
Using roslaunch with Gazebo	62
Getting familiar with Gazebo	63
Environment toolbar	64
World, Insert and Layers panels	66
Joints panel	67
Main window menu bar	68 68
Simulation panel Modifications to the robot URDF	68
Adding the Gazebo tag	69
Specifying color in Gazebo	69
A word about the <visual> and <collision> elements in Gazebo</collision></visual>	69
Verifying a Gazebo model	70
Viewing the URDF in Gazebo	70
Tweaking your model	72
Moving your model around	73
Other ROS simulation environments	74
Summary	75
Chapter 3: Driving Around with TurtleBot	77
Introducing TurtleBot 2	78
Loading TurtleBot 2 simulator software	80
Launching TurtleBot 2 simulator in Gazebo	81
Problems and troubleshooting	83
ROS commands and Gazebo	84
Keyboard teleoperation of TurtleBot 2 in simulation	86
Setting up to control a real TurtleBot 2	87
TurtleBot 2 standalone test	88
Networking the netbook and remote computer	90
Types of networks	90
Network addresses	91
Remote computer network setup	92
Netbook network setup	92
Secure Shell (SSH) connection	93
Summary of network setup	93
Troubleshooting your network connection	94
Testing the TurtleBot 2 system	94
·	96
TurtleBot 2 hardware specifications TurtleBot 2 dashboard	
	96
Moving the real TurtleBot 2	98
Using ROS commands to move TurtleBot 2	98
Using ROS commands to move TurtleBot 2 around	100



1 L	

Writing your first Python script to control TurtleBot 2	101
Introducing rqt tools	104
rqt_graph	105
rqt message publisher and topic monitor	107
TurtleBot's odometry	110
Odom for the simulated TurtleBot 2	114
Real TurtleBot 2's odometry display in rviz	117
TurtleBot 2 automatic docking	118
Introducing TurtleBot 3	120
Loading TurtleBot 3 simulation software	122
Launching TurtleBot 3 simulation in rviz	123
Launching TurtleBot 3 simulation in Gazebo	125
Hardware assembly and testing	129
Loading TurtleBot 3 software	129
Installing remote computer software	129
Installing SBC software	130
Loading Ubuntu MATE	131
Loading ROS packages	133
Loading TurtleBot 3 packages	134
Setting up udev rules for TurtleBot 3	135
Networking TurtleBot 3 and the remote computer	135
Remote computer network setup	136
TurtleBot 3 network setup SSH connection	137
Testing the SSH communication	138
	139 139
Troubleshooting your network connection	
Moving the real TurtleBot 3	140
Using keyboard teleoperation to move TurtleBot 3	141
Summary	143
Chapter 4: Navigating the World with TurtleBot	145
3D vision systems for TurtleBot	146
How these 3D vision sensors work	146
Comparison of 3D sensors	147
Microsoft Kinect	147
ASUS PrimeSense Carmine	149 152
Intel RealSense	153
Hitachi-LG LDS	157
Obstacle avoidance drawbacks	158
Configuring TurtleBot and installing the 3D sensor software	158
Kinect	159
ASUS and PrimeSense	159

Intel RealSense	160
Camera software structure	161
Defining terms	161
Testing the 3D sensor in standalone mode	162
Running ROS nodes for visualization	163
Visual data using Image Viewer	163
Visual data using rviz	165
Navigating with TurtleBot	169
Mapping a room with TurtleBot 2	170
Defining terms	170
Building a map How does TurtleBot accomplish this mapping task?	170 174
Autonomous navigation with TurtleBot 2	175
Defining terms	176
Driving without steering TurtleBot 2	176
rviz control	178
How does TurtleBot accomplish this navigation task?	181
Navigating to a designated location	183
Navigating to waypoints with a Python script using a map	185
Defining TurtleBot's position on a map Defining waypoints on a map	187 188
Using Python code to move TurtleBot	189
TurtleBot at final goal point	191
SLAM for TurtleBot 3	193
Autonomous navigation with TurtleBot 3	195
rqt_reconfigure	197
Exploring ROS navigation further	199
Summary	200
Chapter 5: Creating Your First Robot Arm (in Simulation)	201
Features of Xacro	202
Building an articulated robot arm URDF using Xacro	203
Specifying a namespace	203
Using the Xacro property tag	204
Expanding Xacro	207
Using roslaunch for rrbot	208
Using the Xacro include and macro tags	211
Adding mesh to the robot arm	214
Controlling an articulated robot arm in Gazebo	220
Adding Gazebo-specific elements	221
Fixing the robot arm to the world	222
Viewing the robot arm in Gazebo	223
Adding controls to Xacro	225
Defining transmission elements for joints	225

- [v] -



Table of Contents

Adding a Gazebo ROS control plugin	226
Creating a YAML configuration file	227
Creating a control launch file	228
Controlling your robot arm with the ROS command line	229
Controlling your robot arm with rqt	232 234
Trying more things in rqt	235
Summary Chapter 6: Wobbling Robot Arms Using Joint Control	237
Introducing Baxter	238
Baxter, the research robot	241
Baxter Simulator	242
Baxter's arms	243
Baxter's bend joints	244
Baxter's twist joints	245
Baxter's coordinate frame	246
Control modes for Baxter's arms	247
Baxter's grippers	248
Baxter's arm sensors	249
Loading Baxter software	250
Installing Baxter SDK software	250
Installing Baxter Simulator	252
Configuring the Baxter shell	253
Installing Movelt!	254
Launching Baxter Simulator in Gazebo	255
Bringing Baxter Simulator to life	256
Warm-up exercises	261
Flexing Baxter's arms	263
Untucking Baxter's arms	263
Wobbling arms	265
Controlling arms and grippers with a keyboard Controlling arms and grippers with a joystick	266 267
Controlling arms with a Python script	270
Recording and replaying arm movements	272
Baxter's arms and forward kinematics	273
Joints and joint state publisher	273
Understanding tf	278
A program to move Baxter's arms to a zero angle position	279
Commanding the joint angles directly	281
rviz tf frames	282
Viewing a tf tree of robot elements	283
Introducing Movelt!	284
Planning a move of Baxter's arms with Movelt!	286

Adding objects to a scene	288
Position of objects	290
Planning a move to avoid obstacles with Movelt!	290
Configuring a real Baxter setup	292
Controlling a real Baxter	294
Commanding joint position waypoints	295
Commanding joint torque springs	295
Demonstrating joint velocity	297
Additional examples	297 297
Visual servoing and grasping	297 298
Inverse kinematics	299
Moving Baxter's arms with IK	303
Using a state machine to perform YMCA	308
Summary	
Chapter 7: Making a Robot Fly	311
Introducing quadrotors	312
Why are quadrotors so popular?	313
Defining roll, pitch, and yaw	313
How do quadrotors fly?	314
Components of a quadrotor	316
Adding sensors	317
Quadrotor communications	317
Understanding quadrotor sensors	318
Inertial measurement unit	318
Quadrotor condition sensors	318
Preparing to fly your quadrotor	319
Testing your quadrotor	319
Pre-flight checklist	320
Precautions when flying your quadrotor	320
Following the rules and regulations	321
Using ROS with UAVs	321
Introducing Hector Quadrotor	322
Loading Hector Quadrotor	323
Launching Hector Quadrotor in Gazebo	325 325
Flying Hector outdoors Flying Hector indoors	330
Introducing Crazyflie 2.0	334
Controlling Crazyflie without ROS	336
Communicating using Crazyradio PA	337
Loading Crazyflie ROS software	338
Setting up udev rules for Crazyradio	340
V 1	

Table of Contents

– [vii] –



Table of Contents
Pre-flight check
Flying Crazyflie with teleop Details of teleop_xbox360.launch
Flying with a motion capture system
Flying multiple Crazyflies
Introducing Bebop
Loading bebop_autonomy software Testing Bebop communications
Flying Bebop using commands Take off
Landing
Summary
Chapter 8: Controlling Your Robots with Externa

Flying Crazyflie with teleop	34
Details of teleop_xbox360.launch	34
Flying with a motion capture system	34
Flying multiple Crazyflies	34
Introducing Bebop	34
Loading bebop_autonomy software	34
Testing Bebop communications	35
Flying Bebop using commands	35
Take off Landing	35 35
č	35
Summary	
Chapter 8: Controlling Your Robots with External Devices	35
Creating a custom ROS game controller interface	35
Testing a game controller	35
Alternative test of a game controller	35
Using the ROS joy package	36
Controlling Turtlesim with a custom game controller interface	36
Creating a custom ROS Android device interface	36
Installing Android Studio and tools	36
Installing a ROS–Android development environment	36
Defining terms	37
Introducing ROS–Android development	37
Creating ROS nodes on Arduino or Raspberry Pi	37
Using Arduino	37
Installing Arduino IDE software	37
Installing ROS–Arduino software Ultrasonic sensor control using ROS and Arduino	37 37
Other applications using ROS and Arduino	38
Using Raspberry Pi	38
Installing ROS on the Raspberry Pi	38
Summary	38
Chapter 9: Flying a Mission with Crazyflie	38
Mission components	39
Kinect for Windows v2	39
Crazyflie operation	39
Mission software structure	39
OpenCV and ROS	39
Loading software for the mission	39
Installing libfreenect2	39
Installing iai_kinect2	39

	Table of Contents
Using the iai kinect2 metapackage	402
kinect2_bridge and kinect2_viewer	402
kinect2_calibration	403
Setting up the mission	408
Detecting Crazyflie and a target	409
Identifying markers in a color image	409
Detecting and viewing markers with OpenCV	412
Using Kinect and OpenCV	414
How to track Crazyflie	417
How to control Crazyflie	420
Crazyflie control states	420
Using ROS services to control takeoff and land	421
Using PID control for hover and flight	423
Using an observer node	425
Flying Crazyflie	426
Hovering in place	426
What makes hover work?	427
Flying to a stationary target	428 430
What makes target detection work?	431
Learned lessons	431
Logging messages with rosout and rospy	432
Summary	
Chapter 10: Controlling Baxter with MATLAB©	433
Installing the MATLAB Robotics System Toolbox	434
Check the MATLAB and Robotics System Toolbox versions	434
View the Robotics System Toolbox commands for ROS	434
Using MATLAB Robotics System Toolbox and Baxter Simulator	or 435
Installing Baxter messages in MATLAB	435
Running Baxter Simulator and MATLAB	437
Making Baxter move	440
Summary	444
Index	445

[ix] -