ROS CHEAT SHEET MELODIC

ROS.org

WORKSPACES

Create Workspace

```
mkdir catkin_ws && cd catkin_ws
wstool init src
catkin_make
source devel/setup.bash
```

Add Repo to Workspace

```
roscd; cd ../src
wstool set repo_name \
--git http://github.com/org/repo_name.git \
--version=melodic-devel
wstool up
```

Resolve Dependencies in Workspace

```
sudo rosdep init  # only once
rosdep update
rosdep install --from-paths src --ignore-src \
--rosdistro=${ROS_DISTRO} -y
```

PACKAGES

Create a Package

```
catkin_create_pkg package_name [dependencies ...]
```

Package Folders

`include/package_name`	C++ header files
`src`	Source files. Python libraries in subdirectories
`scripts`	Python nodes and scripts
`msg, srv, action`	Message, Service, and Action definitions

Release Repo Packages

```
catkin_generate_changelog
# review & commit changelogs
catkin_prepare_release
bloom-release --track melodic --ros-distro melodic repo_name
```

Reminders

- Testable logic
- Publish diagnostics
- Desktop dependencies in a separate package

CMakeLists.txt

Skeleton

```
cmake_minimum_required(VERSION 2.8.3)
project(package_name)
find_package(catkin REQUIRED)
catkin_package()
```

Package Dependencies

To use headers or libraries in a package, or to use a package's exported CMake macros, express a build-time dependency:

```
find_package(catkin REQUIRED COMPONENTS roscpp)
```

Tell dependent packages what headers or libraries to pull in when your package is declared as a catkin component:

```
catkin_package(
  INCLUDE_DIRS include
  LIBRARIES ${PROJECT_NAME}
  CATKIN_DEPENDS roscpp)
```

Note that any packages listed as `CATKIN_DEPENDS` dependencies must also be declared as a `<run_depend>` in `package.xml`.

Messages, Services

These go after find_package(), but before catkin_package().
Example:

```
find_package(catkin REQUIRED COMPONENTS message_generation
std_msgs)
add_message_files(FILES MyMessage.msg)
add_service_files(FILES MyService.msg)
generate_messages(DEPENDENCIES std_msgs)
catkin_package(CATKIN_DEPENDS message_runtime std_msgs)ww
```

Build Libraries, Executables

Goes after the `catkin_package()` call.

```
add_library(${PROJECT_NAME} src/main)
add_executable(${PROJECT_NAME}_node src/main)
target_link_libraries(
  ${PROJECT_NAME}_node ${catkin_LIBRARIES})
```

Installation

```
install(TARGETS ${PROJECT_NAME}
  DESTINATION ${CATKIN_PACKAGE_LIB_DESTINATION})
install(TARGETS ${PROJECT_NAME}_node
  DESTINATION ${CATKIN_PACKAGE_BIN_DESTINATION})
install(PROGRAMS scripts/myscript
  DESTINATION ${CATKIN_PACKAGE_BIN_DESTINATION})
install(DIRECTORY launch
  DESTINATION ${CATKIN_PACKAGE_SHARE_DESTINATION})
```

RUNNING SYSTEM

Run ROS using plain:

```
roscore
```

Alternatively, roslaunch will run its own roscore automatically if it can't find one:

```
roslaunch my_package package_launchfile.launch
```

Suppress this behaviour with the `--wait` flag.

Nodes, Topics, Messages

```
rosnode list
rostopic list
rostopic echo cmd_vel
rostopic hz cmd_vel
rostopic info cmd_vel
rosmsg show geometry_msgs/Twist
```

Remote Connection

Master's ROS environment:

- `ROS_IP` or `ROS_HOSTNAME` set to this machine's network address.
- `ROS_MASTER_URI` set to URI containing that IP or hostname.

Your environment:

- `ROS_IP` or `ROS_HOSTNAME` set to your machine's network address.
- `ROS_MASTER_URI` set to the URI from the master.

To debug, check ping from each side to the other, run roswtf on each side.

ROS Console

Adjust using rqt_logger_level and monitor via rqt_console. To enable debug output across sessions, edit the `$HOME/.ros/config/rosconsole.config` and add a line for your package:

```
log4j.logger.ros.package_name=DEBUG
```

And then add the following to your session:

```
export ROSCONSOLE_CONFIG_FILE=$HOME/.ros/config/rosconsole.config
```

Use the roslaunch --screen flag to force all node output to the screen, as if each declared `<node>` had the `output="screen"` attribute.

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