

ROS Tutorials

Non-Beginners: If you're already familiar enough with ROS fuerte (/fuerte) or earlier versions and only want to explore the new build system introduced in groovy (/groovy) and used in hydro (/hydro) and later, called catkin (/catkin), you can go through more in-depth catkin tutorial here (/catkin/Tutorials). However, going over all basic Beginner Level (/ROS/Tutorials#Beginner_Level) tutorials is still recommended for all users to get exposed to new features.


If you are new to Linux: You may find it helpful to first do a quick tutorial on common command line tools for linux. A good one is  here (<http://www.ee.surrey.ac.uk/Teaching/Unix/>).

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1. Core ROS Tutorials

1.1 Beginner Level

1. Installing and Configuring Your ROS Environment (/ROS/Tutorials/InstallingandConfiguringROSEnvironment)

This tutorial walks you through installing ROS and setting up the ROS environment on your computer.
2. Navigating the ROS Filesystem (/ROS/Tutorials/NavigatingTheFilesystem)

This tutorial introduces ROS filesystem concepts, and covers using the roscd, rosls, and rospack (/rospack) commandline tools.
3. Creating a ROS Package (/ROS/Tutorials/CreatingPackage)

This tutorial covers using roscreeate-pkg (/roscreate) or catkin (/catkin) to create a new package, and rospack (/rospack) to list package dependencies.
4. Building a ROS Package (/ROS/Tutorials/BuildingPackages)

This tutorial covers the toolchain to build a package.
5. Understanding ROS Nodes (/ROS/Tutorials/UnderstandingNodes)

This tutorial introduces ROS graph concepts and discusses the use of roscore (/roscore), rosnodet (/rosnodet), and rosrunt (/rosrunt) commandline tools.
6. Understanding ROS Topics (/ROS/Tutorials/UnderstandingTopics)

This tutorial introduces ROS topics as well as using the `rostopic (/rostopic)` and `rqt_plot (/rqt_plot)` commandline tools.

7. Understanding ROS Services and Parameters (</ROS/Tutorials/UnderstandingServicesParams>)

This tutorial introduces ROS services, and parameters as well as using the `rosservice (/rosservice)` and `rosparam (/rosparam)` commandline tools.

8. Using `rqt_console` and `roslaunch` (</ROS/Tutorials/UsingRqtconsoleRoslaunch>)

This tutorial introduces ROS using `rqt_console (/rqt_console)` and `rqt_logger_level (/rqt_logger_level)` for debugging and `roslaunch (/roslaunch)` for starting many nodes at once. If you use ROS fuerte or earlier distros where `rqt (/rqt)` isn't fully available, please see this page with this page (</ROS/Tutorials/UsingRxconsoleRoslaunch>) that uses old rx based tools.

9. Using `roscd` to edit files in ROS (</ROS/Tutorials/UsingRosEd>)

This tutorial shows how to use `roscd (/roscd)` to make editing easier.

10. Creating a ROS msg and srv (</ROS/Tutorials/CreatingMsgAndSrv>)

This tutorial covers how to create and build msg and srv files as well as the `rosmmsg (/rosmmsg)`, `rossrv` and `roscp` commandline tools.

11. Writing a Simple Publisher and Subscriber (C++)

(</ROS/Tutorials/WritingPublisherSubscriber%28c%2B%2B%29>)

This tutorial covers how to write a publisher and subscriber node in C++.

12. Writing a Simple Publisher and Subscriber (Python)

(</ROS/Tutorials/WritingPublisherSubscriber%28python%29>)

This tutorial covers how to write a publisher and subscriber node in python.

13. Examining the Simple Publisher and Subscriber (</ROS/Tutorials/ExaminingPublisherSubscriber>)

This tutorial examines running the simple publisher and subscriber.

14. Writing a Simple Service and Client (C++)

(</ROS/Tutorials/WritingServiceClient%28c%2B%2B%29>)

This tutorial covers how to write a service and client node in C++.

15. Writing a Simple Service and Client (Python)

(</ROS/Tutorials/WritingServiceClient%28python%29>)

This tutorial covers how to write a service and client node in python.

16. Examining the Simple Service and Client (</ROS/Tutorials/ExaminingServiceClient>)

This tutorial examines running the simple service and client.

17. Recording and playing back data

(</ROS/Tutorials/Recording%20and%20playing%20back%20data>)

This tutorial will teach you how to record data from a running ROS system into a .bag file, and then to play back the data to produce similar behavior in a running system.

18. Getting started with `roswtf` (</ROS/Tutorials/Getting%20started%20with%20roswtf>)


Basic introduction to the `roswtf (/roswtf)` tool.

19. Navigating the ROS wiki (</ROS/Tutorials/NavigatingTheWiki>)

This tutorial discusses the layout of the ROS wiki ([ros.org \(/Documentation\)](http://ros.org)) and talks about how to find what you want to know.

20. Where Next? (</ROS/Tutorials/WhereNext>)

This tutorial discusses options for getting to know more about using ROS on real or simulated robots.


Now that you have completed the beginner level tutorials please answer this short  questionnaire (<http://spreadsheets.google.com/viewform?formkey=dGJV0VhyXzd0b0YxRHAXWDdlZmo4cGc6MA>).

1.2 Intermediate Level

More client API tutorials can be found in the relevant package (roscpp (/roscpp/Tutorials), rospy (/rospy/Tutorials), roslisp (/roslisp/Tutorials))

1. Creating a ROS package by hand.
(/ROS/Tutorials/Creating%20a%20Package%20by%20Hand)
This tutorial explains how to manually create a ROS package.
2. Managing System dependencies (/ROS/Tutorials/rosdep)
This explains how to use rosdep (/rosdep) to install system dependencies.
3. Roslaunch tips for large projects
(/ROS/Tutorials/Roslaunch%20tips%20for%20larger%20projects)
This tutorial describes some tips for writing roslaunch files for large projects. The focus is on how to structure launch files so they may be reused as much as possible in different situations. We'll use the 2dnav_pr2 package as a case study.
4. Running ROS across multiple machines (/ROS/Tutorials/MultipleMachines)
This tutorial explains how to start a ROS system using two machines. It explains the use of ROS_MASTER_URI to configure multiple machines to use a single master.
5. Defining Custom Messages (/ROS/Tutorials/DefiningCustomMessages)
This tutorial will show you how to define your own custom message data types using the ROS Message Description Language (/ROS/Message_Description_Language).
6. Using a C++ class in Python
(/ROS/Tutorials/Using%20a%20C%2B%2B%20class%20in%20Python)
This tutorial illustrates a way to use a C++ class with ROS messages in Python.
7. How to Write a Tutorial (/WritingTutorials)
This tutorial covers useful template and macros for writing tutorials, along with example tutorials that are available for guidance on ros.org (/Documentation)

2. ROS Standards

- ROS Developers Guide (/DevelopersGuide) Guidelines for coding style, package layout and much more
-  Standard Units of Measure and Coordinate Conventions (<http://www.ros.org/reps/rep-0103.html>)

3. Tutorials for Other ROS Libraries

- Robot Model (/robot_model_tutorials)
- Visualization (/visualization/Tutorials)
- actionlib (/actionlib_tutorials/Tutorials)
- pluginlib (/pluginlib/Tutorials)

- [nodelets \(/nodelet/Tutorials\)](#)
- [navigation \(/navigation/Tutorials\)](#)
- [ROS-Industrial Tutorials \(/Industrial/Tutorials\)](#)

4. Tutorials for Libraries with ROS Interfaces

- [Stage \(/stage/Tutorials\)](#)
- [TF \(/tf/Tutorials\)](#)
- [PCL with ROS \(/pcl/Tutorials\)](#)

5. External ROS Resources

5.1 External Tutorials

- [ROS Tutorial Video Demos at ANU \(http://www.youtube.com/playlist?list=PLDC89965A56E6A8D6\)](http://www.youtube.com/playlist?list=PLDC89965A56E6A8D6)
- [NooTriX Step-by-Step ROS Tutorials \(http://nootrix.com/category/robotics/robots-software/\)](http://nootrix.com/category/robotics/robots-software/)
- [Jonathan Bohren's ROS Tutorials \(http://jbohren.com/tutorials/\)](http://jbohren.com/tutorials/)
- [Clearpath Robotics' knowledge base \(http://support.clearpathrobotics.com\)](http://support.clearpathrobotics.com)
- [Erle Robotics - Learning ROS \(https://www.youtube.com/watch?v=d5YAJh6Z2B0&list=PL39WpgKDjDfVfiNVG47DBi93wsh2XHKVO\)](https://www.youtube.com/watch?v=d5YAJh6Z2B0&list=PL39WpgKDjDfVfiNVG47DBi93wsh2XHKVO)
- [ROS-Industrial Training Class Curriculum \(http://aeswiki.datasys.swri.edu/rositraining\)](http://aeswiki.datasys.swri.edu/rositraining)

5.2 External Seminar/Lecture

- [Free introductory seminar for enterprises \(http://opensource-robotics.tokyo.jp/?p=355&lang=en\)](http://opensource-robotics.tokyo.jp/?p=355&lang=en) by [TORK \(http://opensource-robotics.tokyo.jp\)](http://opensource-robotics.tokyo.jp) in Tokyo

6. Using ROS on your custom Robot

- [Create your own URDF file \(/urdf/Tutorials\)](#) Creating a custom Universal Robot Description Format file
- [ros_control \(/ros_control\)](#) Use ROS's standard controller framework for interfacing with hardware.
- [Using a URDF in Gazebo \(http://gazebo-sim.org/wiki/Tutorials/1.9/Using_A_URDF_In_Gazebo\)](http://gazebo-sim.org/wiki/Tutorials/1.9/Using_A_URDF_In_Gazebo) Add the necessary tags to get your robot in the Gazebo robotic simulator
- [Setting up MoveIt! \(http://moveit.ros.org/wiki/index.php/Groovy/Quick_Start\)](http://moveit.ros.org/wiki/index.php/Groovy/Quick_Start) Creating the configuration package to use the MoveIt! Motion Planning Framework

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Wiki: ROS/Tutorials (última edición 2016-01-11 16:26:04 efectuada por IsaacSaito (/IsaacSaito))

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