2024/05/14 05:59 1/3 ROS Topics

# **ROS Topics**

This page is a description of all the topics we are using (or plan to use) on the sub.

#### Sensors

#### /orientation

Message: geometry\_msgs/Quaternion

The current orientation of the sub, given as a quaternion. Any code wanting to know the sub's orientation should use this topic, not /orientation/rpy.

#### /orientation/rpy

Message: robosub/Euler

The current orientation of the sub, given in roll, pitch, yaw. This is meant just for human readability of the sub's orientation, code should use the /orientation topic.

#### /depth

Message: std\_msgs/Float32
The current depth of the sub.

#### **Movement**

#### /thruster

Message: robosub/thruster

Dynamic array of commands going to the thrusters. Order of the thrusters is dependent on their order in the settings file.

#### /control

Message: robosub/control

Send messages to this topic to move the sub around, the control system subscribes to this topic.

#### /joystick\_driver

Message: robosub/joystick This is the raw joystick state, published by the joystick driver. Shows the

current state of all axes and buttons on the joystick.

#### **Vision**

#### /camera/(left|right|bottom)/image

Message: wfov\_camera\_msgs/WFOVImage

Images from our cameras.

#### /vision/buoy/(red|green|yellow)

Message: robosub/visionPosArray

Describes where the buoy is in the sub's view.

#### /vision/start gate

Message: robosub/visionPosArray

Describes how many posts of the start gate can be seen and where they are located in the sub's view.

## **Hydrophones**

#### /hydrophone/[Frequency]/deltas

Message: Duplicated for all frequencies in the pool. Contains the latest time deltas between the reference and other 3 hydrophones.

Header header
Time d1
Time d2
Time d3

## /hydrophone/[Frequency]/timestamps

Message: Duplicated for all frequencies in the pool. Contains the latest timestamps recorded by the system.

Header header
Time ref
Time t1
Time t2
Time t3

2024/05/14 05:59 3/3 ROS Topics

### /hydrophone/[Frequency]/debug

Message: Used for debugging the hydrophone system.

Header header
Int64 frequency
Int64 avg\_sig\_strength
Float64 approx\_angle

## /hydrophone/[Frequency]/output

Message: Used for sending the final result of the Trilaterization calculations.

From:

https://robosub.eecs.wsu.edu/wiki/ - Palouse RoboSub Technical Documentation

Permanent link:

https://robosub.eecs.wsu.edu/wiki/cs/topics\_list/start?rev=1481073065

Last update: 2016/12/06 17:11