

# 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/pretty**

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

### **/hydrophones/[Frequency]/deltas**

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

```
Header header
duration d1
duration d2
duration d3
```

### **/hydrophones/[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
```

## /hydrophones/[Frequency]/debug

Message: Used for debugging the hydrophone system.

```
Header header
Int64 frequency
Int64 avg_sig_strength
Float64 approx_angle
```

## /hydrophones/[Frequency]/output/direction

Message: [robosub/Euler](#)

Used for sending the angle from the forward direction to the pinger. Roll will always be zero while Pitch and Yaw should be filled out.

## /hydrophones/[Frequency]/output/location

Message: [geometry\\_msgs/Point](#)

Used for sending the final result of the Trilaterization calculations.

From:

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

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