

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
```

/hydrophone/[Frequency]/debug

Message: Used for debugging the hydrophone system.

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

/hydrophone/[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.

/hydrophone/[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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