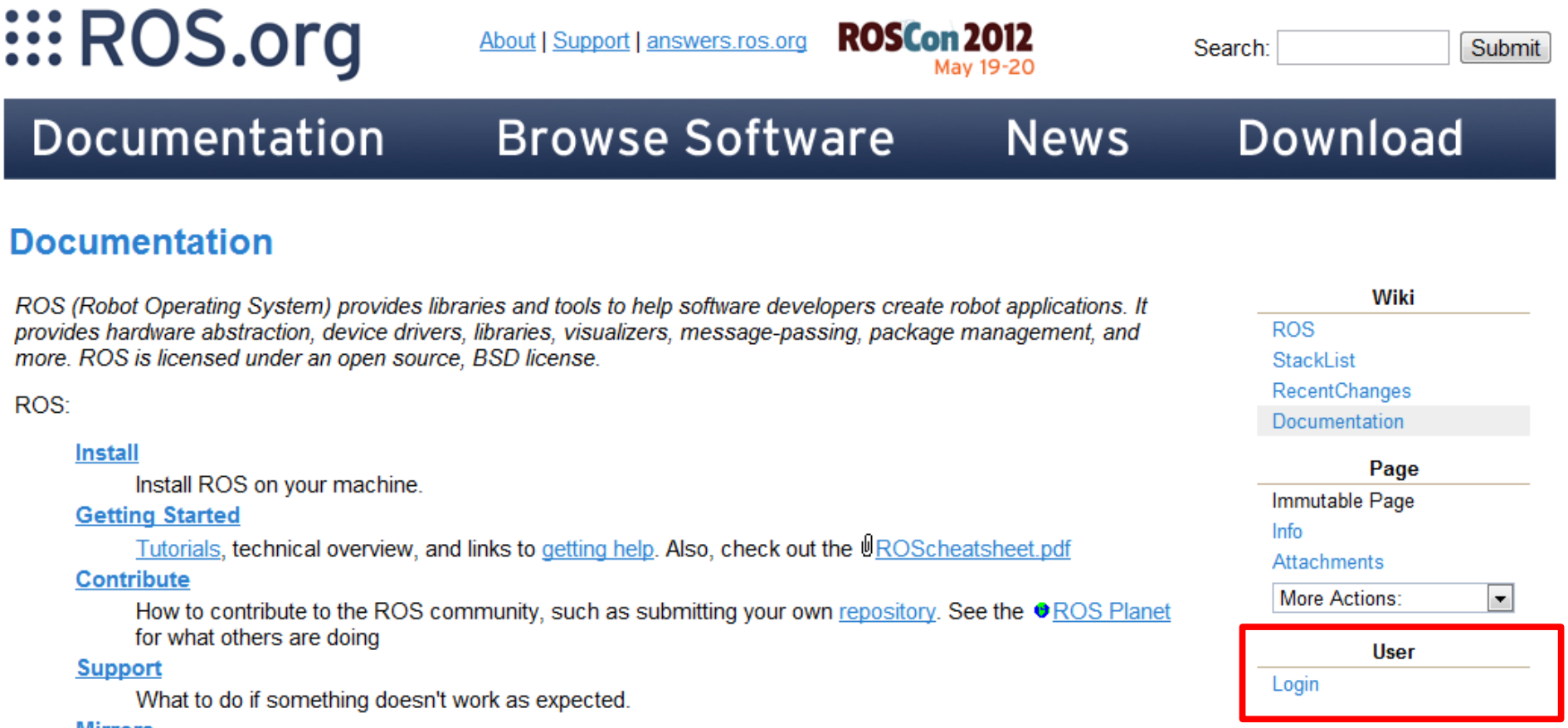
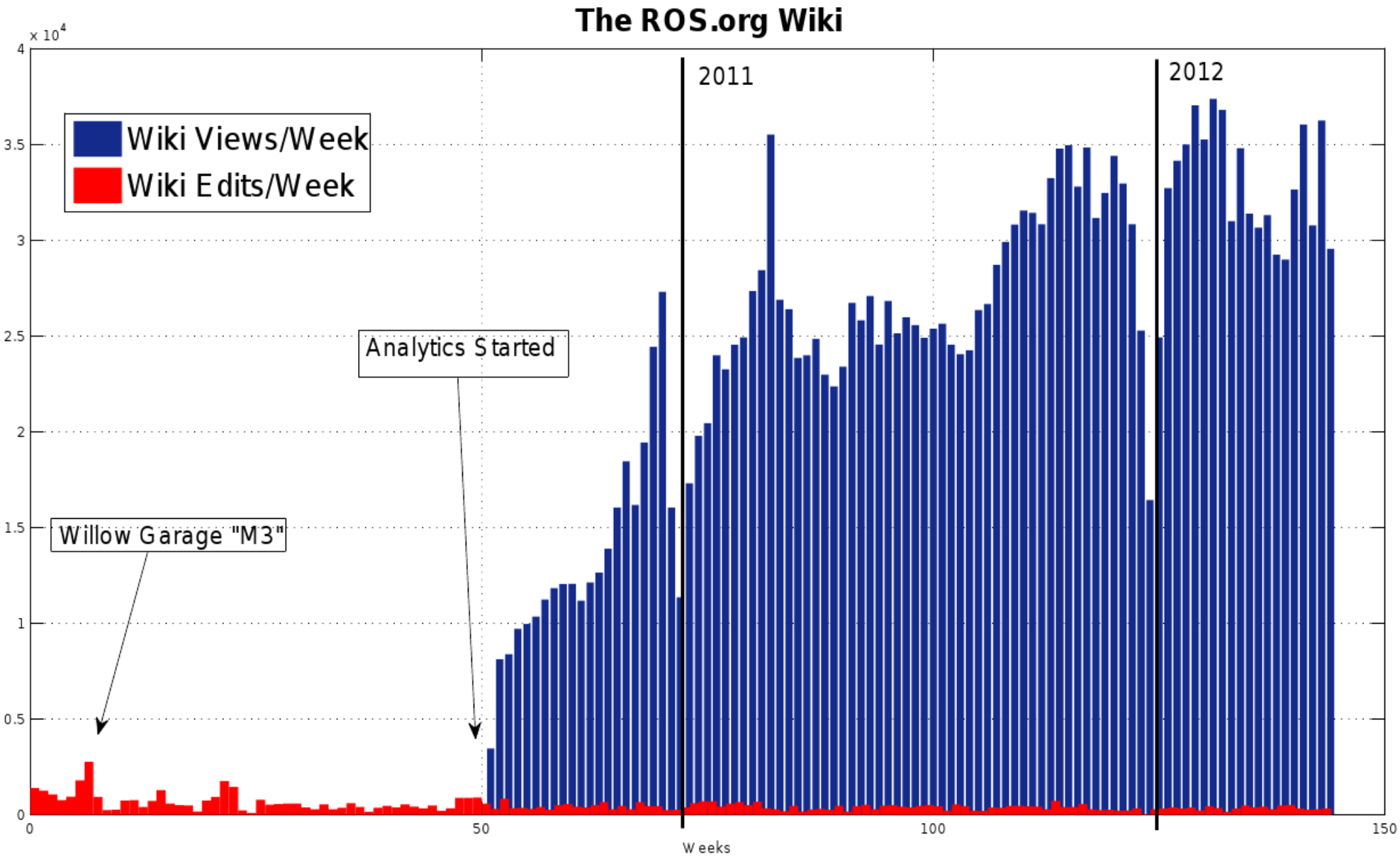
WIKI

ROSCon 2012

WIKI = EDITABLE




The ROS.org Wiki
x 10^4
4
3.5
3
2.5
2
1.5
1
0.5
0
2011
2012
Wiki Views/Week
Wiki Edits/Week
Analytics Started
Willow Garage "M3"
0
50
100
150
Weeks

IF YOU SEE SOMETHING

~~SAY SOMETHING~~

FIX IT!

"BY OUR POWERS COMBINED..."

Package/Stack Naming

- The wiki has a flat name space
  - Look before you collide
- Be specific
  - Avoid utils, common, etc
- Try not to use acronyms
  - If you insist, document with relevant key words

Documentation

- Fill out the manifest.xml/stack.xml

- Don't create a wiki page if you're not going to create documentation
  - ROS Browse will help others find packages without documentation

- Follow the wiki style guide
  - http://ros.org/wiki/StyleGuide

tf

geometry: *angles* | *eigen_conversions* | *tf* | *tf_conversions*

1. Package Summary

tf is a package that lets the user keep track of multiple coordinate frames over time. tf maintains the relationship between coordinate frames in a tree structure buffered in time, and lets the user transform points, vectors, etc between any two coordinate frames at any desired point in time.

- Author: Tully Foote, Eitan Marder-Eppstein, Wim Meeussen
- License: BSD
- Repository: wg-kforge
- Source: hg https://kforge.ros.org/geometry/geometry

Contents

1. Package Summary
2. What does tf do? Why should I use tf?
3. Tutorials
4. Code API Overview
5. Frequently asked questions
6. Command-line Tools
    1. tf_monitor
    2. tf_echo
    3. static_transform_publisher
    4. view_frames
    5. roswtf plugin
7. Nodes

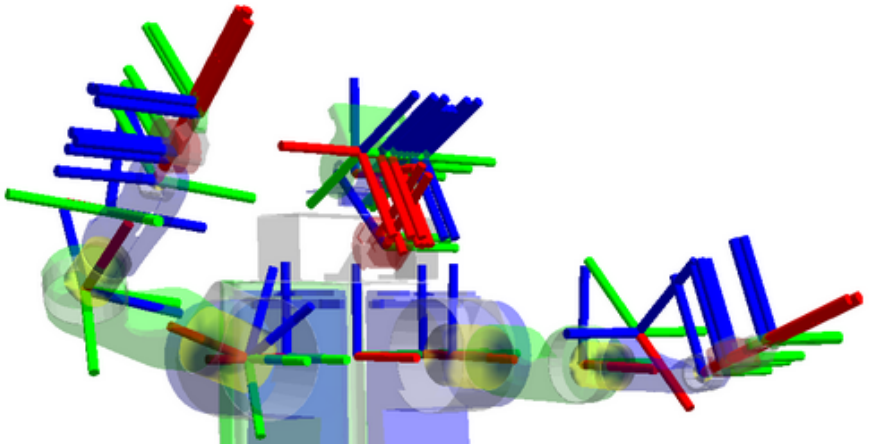
Package Links

Code API
- diamondback
- electric
- fuerte
- unstable

Msg/Srv API
- diamondback
- electric
- fuerte
- unstable

Tutorials
Troubleshooting
FAQ
Reviews (doc reviewed)

Dependencies (10)
Used by (721)



Wiki Macros

http://ros.org/wiki/WikiMacros

- GetTaggedCode
- Version
- Clearsilver/IncludeCSTemplate
- SeeSaw
- Linking

GetTaggedCode

<<GetTaggedCode(code_uri,code_tag,show_uri,no_tag_newlines,global_lines)>>

In Comment use:

%Tag(TAG)%

%EndTag(TAG)%

Version

<<Version()>>

win_ros

win_ros: *mingw_cross* | *msvc_hudson* | *msvc_runtime* | *msvc_sdk* | *win_appupdater* | *win_boost* | *win_bzip2* | *win_empy* | *win_patches* | *win_pymercurial* | *win_pyyaml* | *win_roscd* | *win_roscpp_tutorials* | *win_rosinstall*

1. Stack Summary

Setup and utilities for ros on windows.

- Author: Maintained by Daniel Stonier
- License: BSD
- Repository: yujin-ros-pkg
- Source: git https://github.com/stonier/win_ros.git

cturtle | diamondback | electric | fuerte

Stack Links

Tutorials
Roadmap
Reviews (experimental)

Dependencies (4)

Version

<<Version(release_name)>>

Diamondback Example:

Options:

`-l, --latch` **New in Diamondback**
Enable latch mode. Latching mode is the *default* when using command-line arguments.

`-r RATE`
Enable *rate mode*. Rate mode is the *default* (10hz) when using piped or file input.

`-1, --once`
Enable *once mode*.

`-f FILE` **New in Diamondback**
Read message fields from YAML file. YAML syntax is equivalent to output of `rostopic echo`. Messages are separated using YAML document separator `---`. To use only the first message in a file, use the `--latch` option.

Clearsilver

#!clearsilver parser_location

example NodeAPI (#!clearsilver CS/NodeAPI):

2. Nodes

2.1 photo_node

The usb camera node interfaces with standard USB cameras (e.g. the Logitech Quickcam) using libusb_cam and publishes images as sensor_msgs::Image.

2.1.1 Services

`get_config` (photo/GetConfig)

queries the value of a parameter

`set_config` (photo/SetConfig)

sets the value for a given parameter

`capture` (photo/Capture)

Image width

IncludeCSTemplate

<<IncludeCSTemplate(template_location)>>

Tutorial Example:

Save Changes | Preview | Check Spelling | Cancel | Trivial change

```
####################################
##FILL ME IN
####################################
## links to any required tutorials
## note.0= [[ROS/Tutorials/ExaminingPublisherSubscriber|examining the simple
publisher and subscriber]]
## descriptive title for the tutorial
## title = Writing a Simple Service and Client
## multi-line description to be displayed in search
## description = This tutorial covers how to write a service and client node in C++.
## the next tutorial description (optional)
## next =
## links to next tutorial (optional)
## next.0.link= [[roscpp_tutorials/Tutorials/Parameters|Using Parameters in roscpp]]
## next.1.link=
## what level user is this tutorial for
## level= BeginnerCategory
####################################

<<IncludeCSTemplate(TutorialCSHeaderTemplate)>>
```

Seesaw

Allows you to toggle content visibility

<<SeeSaw(section="sshhelp1",toshow="(ssh help)")>>

{{{#!wiki seesaw sshhelp1

<<Include(turtlebot/help/ssh)>><
>

}}}

Linking

<<MsgLink(package/name)>>

<<SrvLink(package/name)>>

<<KforgeTracLink(repo package)>>

<<TracLink(repo package)>>

<<LurkerLink(message/blah)>>

ROS Promotions

Promotions are a feature of Google custom search on the ROS wiki

Search Results

Refine results: **All results** ros-users ros reps ros api docs ros answers ros wiki docs all ros.org

About 33,700 results (0.16 seconds)

Looking for a **transformation** library?
tf maintains the relationship between coordinate frames in a tree structure buffered in time.
http://www.ros.org/wiki/tf

tf/Tutorials
www.ros.org/wiki/tf/Tutorials/Introduction%20to%20tf
Labeled all ros.org ros wiki docs

tf
www.ros.org/wiki/tf
Labeled all ros.org ros wiki docs