

Node Manager – Cheat Sheet

Start

Start roscore in advance

Run node_manager

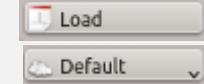
- `$ roscore`
- `$ node_manager`

Loading

Load Launchfile

Default configuration Launchfile

- Press *Load*
- Press *default*



Launching



Run loaded Launchfile

Use Capability-View

- Press *Play on toplevel hierarchy*
- Press *on* (if default cfg)



Tools

Nodes

Topics

Services

Parameter

Nodes tab

Topics tab

Services tab

Parameter tab



Rqt Button



Run Button

- Play/Stop loaded nodes
- Monitor or publish topics
- Call Services
- Get or set Parameter server
- Start rqt
- Start any rosnode

Configure

Launchfiles
Capability_group parameter

- Cfg is stored in launch file
- Use `<param name="capability_group" value="my_group"/>` to group nodes to capabilities

Robots Parameter
Capabilities Parameter

- Name and description of host
- Name and description of capability-groups

Installation

Debian install

- `$ sudo apt-get install ros-hydro-multimaster-fkie`

Github

- `git clone https://github.com/fkie/multimaster_fkie.git`

Help

Ros Wiki
Github Wiki
Contact

- http://wiki.ros.org/node_manager_fkie
- http://fkie.github.io/multimaster_fkie/node_manager.html
- alexander.tiderko@gmail.com