

## ROS PKG

seacat\_terre  
seacat\_engin  
usv  
cameras  
winch

## ROS parameters

sys\_manage/ip  
seacat\_interface/ip  
driver\_power\_generator/can\_name  
driver\_adam\_seacat/ip  
driver\_adam\_seacat/port  
driver\_nmea/ip  
driver\_nmea/port  
driver\_brain\_box/ip  
driver\_brain\_box/port  
driver\_esc\_piktronic/com\_port  
driver\_esc\_piktronic/com\_port  
rosserial\_arduino\_esc\_piktronic/port  
rosserial\_arduino\_esc\_piktronic/ baud  
driver\_winch/winchip  
driver\_winch/winchip\_port  
seacat\_ctrl/m Iz, C7, rpm\_max, I, dt\_ctrl\_ms  
seacat\_ctrl/motor\_/left/right\_rev  
driver\_nmea/gps\_gyro\_dev, baud  
driver\_nmea/ais\_dev, baud

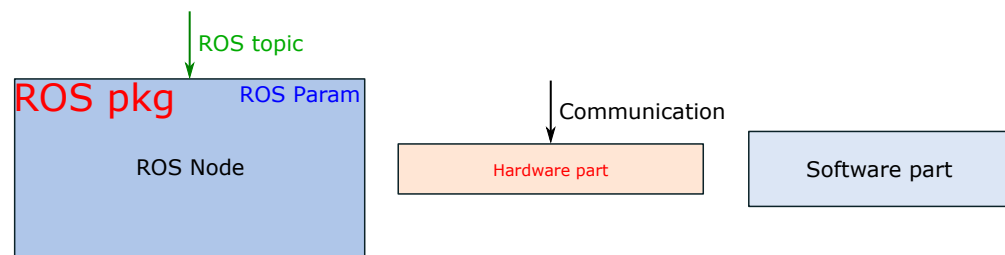
## NMEA FRAMES

**Gyrocompas sentences**  
HDG, HDT, HDM  
**GPS sentences**  
DTM, GGA, GLL, GSA, GSV, RMC, VTG, ZDA  
**AIS sentences**  
RMC, GSV, GSA, GGA, GLL, VTG, VDO, VDM, TXT, DSC, HDG, VHW, DPT, VLW, MWD, MWV, MTW

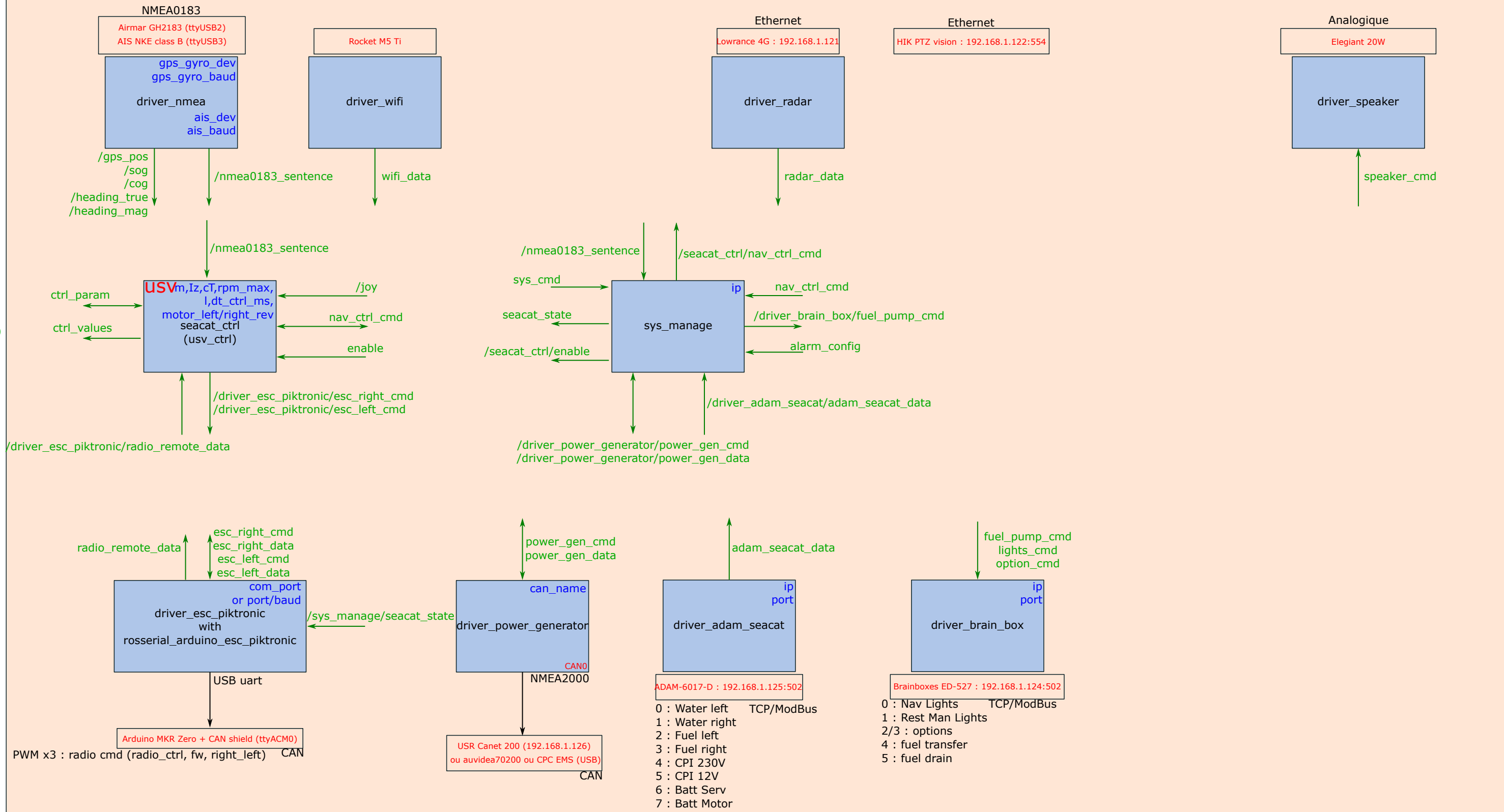
## ROS MSG

**winch\_cmd**  
bool reel\_dir  
bool reel\_on  
bool actuator\_dir  
**nav\_ctrl\_cmd**  
uint16 mode\_ctrl (autopilot, joy, gps+speed, head+speed, debug)  
bool joy\_ctrl  
sensor\_msgs/NavSatFix position\_goto\_order  
float32 speed\_order  
float32 head\_order  
**fuel\_pump\_cmd**  
drain\_pump  
transfer\_pump  
(std\_msgs/Bool)  
**lights\_cmd**  
nav\_light  
restricted\_man\_light  
mooring\_light  
beacon\_light  
(std\_msgs/Bool)  
**speaker\_cmd**  
speaker\_on  
(std\_msgs/Bool)  
**power\_gen\_cmd**  
ask\_startup  
(std\_msgs/Bool)  
**esc\_cmd**  
bool enable  
bool reverse  
int16 speed  
uint8 power\_limit  
**winch\_cmd**  
uint8 lin\_speed  
int16 unroll\_limit  
bool set\_limits  
bool reel\_dir  
bool reel\_on  
**ctrl\_param**  
bool save\_param  
float32 kff\_v  
float32 kp\_v  
float32 ki\_v  
float32 isat\_v  
float32 kp\_z  
float32 ki\_z  
float32 kd\_z  
float32 isat\_in\_z  
float32 isat\_out\_z  
float32 ithresh\_z  
d\_stop  
d\_slow  
pw\_fast  
pw\_slow  
**sys\_cmd**  
uint8 cmd  
**actuator\_cmd**  
bool actuator\_dir  
bool actuator\_on  
**option\_cmd**  
uint8 opt\_num  
bool cmd  
**power\_gen\_data**  
voltage  
current  
power  
(std\_msgs/Float32)  
power\_on  
(std\_msgs/Bool)  
temperature  
inv\_temp  
(std\_msgs/Int16)  
system\_state  
error\_code  
(std\_msgs/UInt8)  
**esc\_data**  
speed  
speed\_setpoint  
voltage  
current  
power  
motor\_temp  
esc\_temp  
(std\_msgs/Float32)  
status  
(std\_msgs/UInt16)  
**adam\_seacat\_data**  
eau\_babord  
eau\_tribord  
(std\_msgs/Bool)  
fuel\_babord  
fuel\_tribord  
(std\_msgs/Float32)  
alarm\_cp12  
alarm\_cp11  
(std\_msgs/Bool)  
voltage\_batt\_serv  
voltage\_batt\_mot  
(std\_msgs/Float32)  
**radar\_data**  
status  
(std\_msgs/Bool)  
**cam\_front\_data**  
status  
(std\_msgs/Bool)  
**cam\_360\_data**  
status  
(std\_msgs/Bool)  
**winch\_data**  
bool status  
float32 cable\_length  
uint8 platform\_pos  
uint16 motor\_rpm  
bool platform\_pos  
bool roll\_end  
bool unroll\_end  
**radio\_remote\_data**  
bool cable\_ctrl\_remote  
uint16 ppm\_fw  
uint16 ppm\_st  
int16 rpm\_order\_right  
int16 rpm\_order\_left  
**ctrl\_values**  
float32 v\_des, v\_mes  
float32 err\_v  
float32 ff\_v, p\_v, i\_v  
float32 psi\_des, psi\_mes  
float32 err\_z, dpsl\_fil  
float32 p\_z, i\_z, d\_z  
float32 f\_v, t\_z  
**seacat\_state**  
int8 state  
uint8 err\_code  
**actuator\_data**  
uint8 platform\_pos

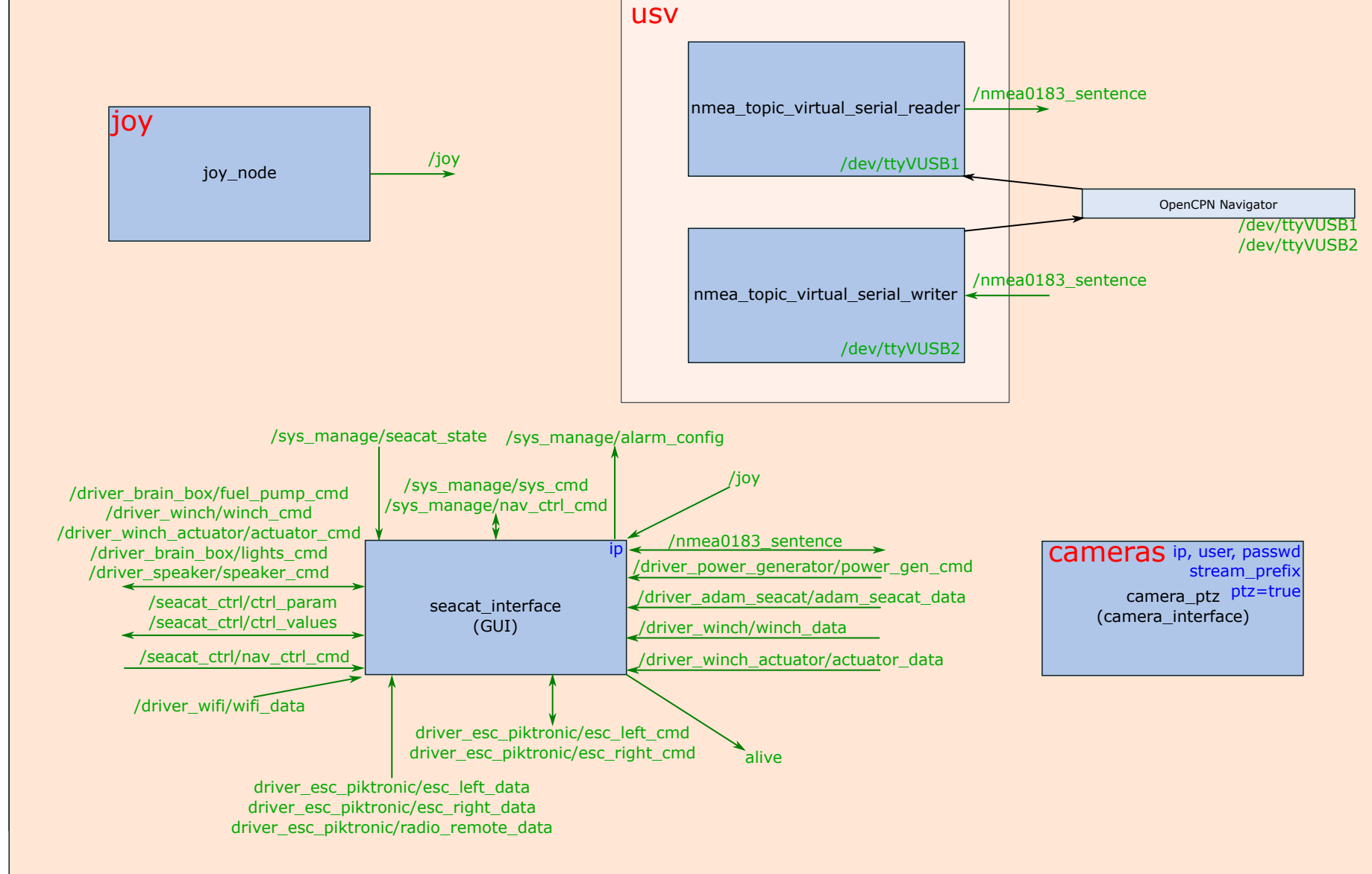
**alive**  
bool  
**enable**  
bool  
**nmea0183\_sentence**  
nmea\_msgs/Sentence  
**joy**  
sensor\_msgs/Joy  
**alarm\_config**  
alarm\_array (alarm[])  
pos\_home (sensor\_msgs/NavSatFix)  
**alarm**  
alarm\_id  
action\_id  
(std\_msgs/UInt8)  
param (std\_msgs/Float32)



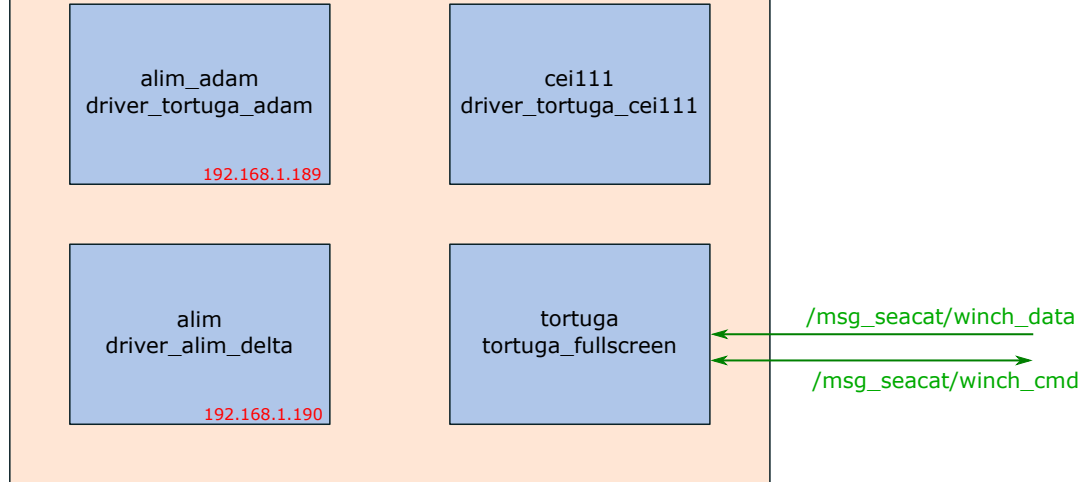
seacat\_engin : 192.168.1.100



seacat\_terre : 192.168.1.101

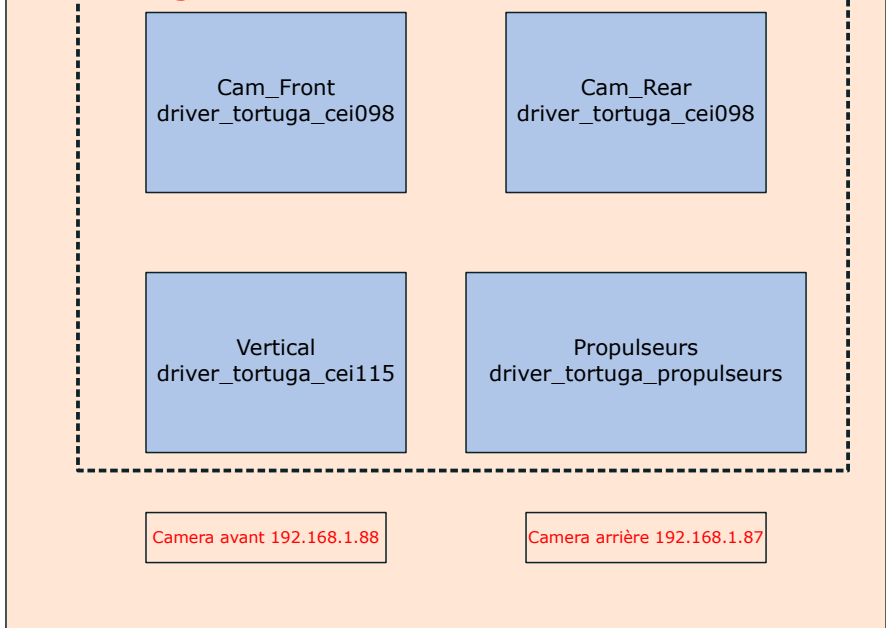


tortuga\_console : 192.168.1.181



tortuga bas

tortuga bas : 192.168.1.180



winch

