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# **sphinx<sub>ros</sub>***Documentation*

***Release 0.1.0rc1.dev5+gc85cdfb***

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## Contents:

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<b>1</b>	<b>Getting started</b>	<b>3</b>
1.1	Configuration . . . . .	3
1.2	Directives . . . . .	3
1.3	Roles . . . . .	4
1.4	Package example . . . . .	5
1.5	Indices . . . . .	8
<b>2</b>	<b>Modules</b>	<b>9</b>
2.1	sphinx_ros module . . . . .	9
2.2	sphinx_ros.domain module . . . . .	9
2.3	sphinx_ros.indices module . . . . .	10
2.4	sphinx_ros.directives module . . . . .	10
2.5	sphinx_ros.xref_role module . . . . .	11
<b>3</b>	<b>Indices and tables</b>	<b>13</b>
	<b>Python Module Index</b>	<b>15</b>
	<b>Package Index</b>	<b>17</b>
	<b>Message Type Index</b>	<b>19</b>
	<b>Index</b>	<b>21</b>



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- *Configuration*
- *Directives*
- *Roles*
- *Package example*
- *Indices*

## 1.1 Configuration

### **ros\_msg\_reference\_version**

The used ROS (Robot Operating System) version to use when referencing to default message types, e.g. 'kinetic' or 'melodic'. It defaults to 'melodic' and is set to 'kinetic' for this documentation.

### **ros\_add\_package\_names**

Can be set to `False` to prevent package names from showing in message, service, or action type descriptions. Defaults to `True`.

## 1.2 Directives

**.. ros:package:: package**

Similar to the Python domain's `.. py:module::` directive. It will not output any nodes, but serves to set the context's ROS package and will produce a hyperlink target and an index entry for `package`. Defined packages can be referenced with `:ros:pkg:`package``.

### **Options**

- **noindex** – Prevents adding the package to the index, basically turns this directive into `ros:currentpackage`.
- **deprecated** – Flags this package as deprecated. This will show up in the index.

**.. ros:currentpackage:: package**

Similar to the Python domain's `.. py:currentmodule::` directive. It will not produce any nodes nor an index entry but will set the context's ROS package such that Sphinx knows that we are documenting stuff in that package.

This directive has no options.

**.. ros:message:: message**

Can be used to describe a message type definition. It will create an index entry and a hyperlink target for this message type. It will also output nodes to describe the message.

#### Options

- **noindex** – Prevents adding the message to the index and creating a hyperlink target node.
- **deprecated** – Flags this message as deprecated. This will show up in the index.

Two flags are recognized in this directive's content: `:msg_param <name>:` and `:msg_paramtype <name>:`. The former defines a parameter that is contained in the message, the latter defines the same parameter's type. All parameters will be grouped in a list.

**.. ros:service:: service**

Can be used to describe a service type definition. It will create a hyperlink target for the service type. It will also output nodes to describe the service.

#### Options

- **noindex** – Prevents creating a hyperlink target node for the service.
- **deprecated** – Flags this service as deprecated.

Four flags are recognized in this directive's content: `:req_param <name>:` and `:req_paramtype <name>:` work similar to the flags of the message directive, but they add parameters to the service's request. `:resp_param <name>:` and `:resp_paramtype <name>:` do the same for the service's response.

**.. ros:action:: action**

Can be used to describe an action type definition. It will create a hyperlink target for the action type. It will also output nodes to describe the action.

#### Options

- **noindex** – Prevents creating a hyperlink target node for the action.
- **deprecated** – Flags this action as deprecated.

Six flags are recognized in this directive's content: `:goal_param <name>:` and `:goal_paramtype <name>:` work similar to the flags of the message directive, but they add parameters to the action's goal. `:result_param <name>:` and `:result_paramtype <name>:` do the same for the action's result. `:feedback_param <name>:` and `:feedback_paramtype <name>:` do the same for the action's feedback.

## 1.3 Roles

**:ros:pkg:**

Can be used to reference a defined package.



**:ros:msg:**

Can be used to reference a defined message type. Adding the ~ prefix to the message name will let it print *only* the message name and not the package name. First it is checked if the message is one of the ROS primitive message types (**bool**, **int8**, **uint8**, **int16**, **uint16**, **int32**, **uint32**, **int64**, **uint64**, **float32**, **float64**, **string**, **time**, **duration**). If so, it will not link anywhere. If it is of the type **Header** or it is a message in one of the default ROS message packages, it will link to the proper documentation, keeping into account the ROS version set by *ros\_msg\_reference\_version*.

The default ROS message packages that are correctly handled as of now are: **std\_msgs**, **geometry\_msgs**, and **sensor\_msgs**.

**:ros:srv:**

Can be used to reference a defined service type. Adding the ~ prefix to the service name will let it print *only* the service name and not the package name.

**:ros:act:**

Can be used to reference a defined action type. Adding the ~ prefix to the action name will let it print *only* the action name and not the package name.

## 1.4 Package example

### 1.4.1 The `sphinx_ros_example` package.

- *Dependencies*
- *Messages*
- *Services*
- *Actions*

The `sphinx_ros_example` package contains all sorts of ROS objects, purely for example purposes. Objects can be referenced just like the familiar default Sphinx references, e.g. `sphinx_ros_example/Foo` will link the proper message, and `sphinx_ros_example/Bar` will link to the proper service. We can also use the ~ to prevent displaying the package name, e.g. `Foo` still points to the right message.

**Author** J. Doe

**Maintainer** J. Doe

**Links**

- [Repository](#)
- [Bugtracker](#)

**Version** 1.2

**License** MIT

### Dependencies

**Build**

- `message_generation`
- `std_msgs`

**Build export** std\_msgs

**Build tool** catkin

**Execution**

- message\_runtime
- std\_msgs

## Messages

**message** sphinx\_ros\_example/Foo

**Parameters**

- **header** (Header) – Header of the message.
- **pose** (geometry\_msgs/Pose) – The 3D pose of the foo that is detected.
- **color** (string) – The color of the foo.

## Services

**service** sphinx\_ros\_example/Bar

**Request parameters** **one\_way** (sphinx\_ros\_example/Foo) – The request parameter.

**Response parameters**

- **or\_another** (int8) – The response parameter.
- **highway** (uint16) – The correct way.

## Actions

**action** sphinx\_ros\_example/FooBar

**Goal parameters** **setpoint** (geometry\_msgs/Point) – The setpoint to reach.

**Result parameters** **steady\_state\_error** (geometry\_msgs/Point) – Error between achieved point and setpoint.

**Feedback parameters**

- **tracking\_error** (geometry\_msgs/Point) – Error between ideal trajectory and current trajectory.
- **power** (float32[]) – Current power usage per joint.

Listing 1: Source

```
.. ros:package:: sphinx_ros_example

#####
The ``sphinx_ros_example`` package.
#####

.. contents::
   :local:
   :depth: 1
```

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The `:ros:pkg:`sphinx_ros_example`` package contains all sorts of ROS objects, purely for example purposes. Objects can be referenced just like the familiar default Sphinx references, e.g. `:ros:msg:`sphinx_ros_example/Foo`` will link the proper message, and `:ros:srv:`sphinx_ros_example/Bar`` will link to the proper service. We can also use the ```~``` to prevent displaying the package name, e.g. `:ros:msg:`~sphinx_ros_example/Foo`` still points to the right message.

```
:Author: `J. Doe <j.doe@mail.com>`_
```

```
:Maintainer: `J. Doe <j.doe@mail.com>`_
```

```
:Links: * `Repository <http://github.com/user/repo>`_
        * `Bugtracker <http://github.com/user/repo/issues>`_
```

```
:Version: 1.2
```

```
:License: MIT
```

```
*****
```

```
Dependencies
```

```
*****
```

```
:Build: * :ros:pkg:`message_generation`
        * :ros:pkg:`std_msgs`
```

```
:Build export: :ros:pkg:`std_msgs`
```

```
:Build tool: :ros:pkg:`catkin`
```

```
:Execution: * :ros:pkg:`message_runtime`
            * :ros:pkg:`std_msgs`
```

```
*****
```

```
Messages
```

```
*****
```

```
.. ros:message:: Foo
```

```
    :msg_param header: Header of the message.
    :msg_paramtype header: :ros:msg:`Header`
    :msg_param pose: The 3D pose of the foo that is detected.
    :msg_paramtype pose: :ros:msg:`geometry_msgs/Pose`
    :msg_param color: The color of the foo.
    :msg_paramtype color: :ros:msg:`string`
```

```
*****
```

```
Services
```

```
*****
```

```
.. ros:service:: Bar
```

```
    :req_param one_way: The request parameter.
```

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```
:req_paramtype one_way: :ros:msg:`sphinx_ros_example/Foo`
:resp_param or_another: The response parameter.
:resp_paramtype or_another: :ros:msg:`int8`
:resp_param highway: The correct way.
:resp_paramtype highway: :ros:msg:`uint16`

*****
Actions
*****

.. ros:action:: FooBar

:goal_param setpoint: The setpoint to reach.
:goal_paramtype setpoint: :ros:msg:`geometry_msgs/Point`
:result_param steady_state_error: Error between achieved point and setpoint.
:result_paramtype steady_state_error: :ros:msg:`geometry_msgs/Point`
:feedback_param tracking_error: Error between ideal trajectory and current
                                trajectory.
:feedback_paramtype tracking_error: :ros:msg:`geometry_msgs/Point`
:feedback_param power: Current power usage per joint.
:feedback_paramtype power: :ros:msg:`float32[]`
```

## 1.5 Indices

These indices are generated by this Sphinx extension. They are autogenerated and can be referenced with `:ref:`ros-pkgindex`` and `:ref:`ros-msgindex`` respectively.

- `ros-pkgindex`
- `ros-msgindex`

## 2.1 sphinx\_ros module

Sphinx extension adding several directives to document ROS packages.

`sphinx_ros.setup(app)`

Adds the ROS domain to the Sphinx application and the labels to the ROS indices to the standard domain. It also adds the configuration values `ros_add_package_names` and `ros_msg_reference_version`.

**Parameters** `app` (`sphinx.application.Sphinx`) – The Sphinx application

## 2.2 sphinx\_ros.domain module

This module defines the ROS domain. It defines three object types (messages, services, and actions) and registers the roles and directives in the Sphinx application.

**class** `sphinx_ros.domain.RosDomain(env)`

The actual domain class.

**add\_package** (`name`, `deprecated`)

Adds a package to the domain data.

**Parameters**

- **name** (`str`) – The name of the package
- **deprecated** (`bool`) – Indicates whether the package is deprecated.

**Returns** The unique anchor of the package.

**Return type** `str`

**find\_obj** (`env`, `pkgname`, `name`, `type`, `searchmode=0`)

Find a ROS object for `name`, perhaps using `pkgname`.

## 2.3 sphinx<sub>ros</sub>.indices module

This modules defines the indices added to Sphinx.

**class** sphinx<sub>ros</sub>.indices.**RosMessageIndex** (*domain*)  
Index listing the documented message types.

**class** sphinx<sub>ros</sub>.indices.**RosPackageIndex** (*domain*)  
Index listing the documented packages.

## 2.4 sphinx<sub>ros</sub>.directives module

**class** sphinx<sub>ros</sub>.directives.**RosActionDirective** (*name, arguments, options, content, lineno, content\_offset, block\_text, state, state\_machine*)

Description of a ROS action type.

**class** sphinx<sub>ros</sub>.directives.**RosCurrentPackageDirective** (*name, arguments, options, content, lineno, content\_offset, block\_text, state, state\_machine*)

This directive is just to tell Sphinx that we're documenting stuff in this package, but links to this package will not lead here.

**class** sphinx<sub>ros</sub>.directives.**RosMessageDirective** (*name, arguments, options, content, lineno, content\_offset, block\_text, state, state\_machine*)

Description of a ROS message type.

**class** sphinx<sub>ros</sub>.directives.**RosObject** (*name, arguments, options, content, lineno, content\_offset, block\_text, state, state\_machine*)

Description of a general ROS object.

**add\_object\_to\_domain\_data** (*fullname, obj\_type*)  
Add the object to the object lists of the ROS domain data.

**get\_index\_text** (*pkgname, name*)  
Return the text for the index entry of the object.

**get\_object\_type\_prefix** ()  
May return an optional name prefix that defines object type, e.g. 'msg' or 'srv'.

**get\_signature\_prefix** (*sig*)  
May return a prefix to put before the object name in the signature.

**handle\_signature** (*sig, signode*)  
Transform a ROS signature into rST nodes.

Return (fully qualified name of the thing, package name if any).

If inside a package, the current package name is handled intelligently: \* it is stripped from the displayed name if present \* it is added to the full name (return value) if not present

**class** sphinx<sub>ros</sub>.directives.**RosPackageDirective** (*name, arguments, options, content, lineno, content\_offset, block\_text, state, state\_machine*)

Directive to mark description of a new package.

```
class sphinx_ros.directives.RosServiceDirective (name, arguments, options, content,  
                                                lineno, content_offset, block_text, state,  
                                                state_machine)
```

Description of a ROS service type.

```
class sphinx_ros.directives.RosType (name, arguments, options, content, lineno, content_offset,  
                                     block_text, state, state_machine)
```

Super class for messages, services, and actions.

## 2.5 sphinx\_ros.xref\_role module





## CHAPTER 3

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### Indices and tables

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- [genindex](#)
- [modindex](#)
- [ros-pkgindex](#)
- [ros-msgindex](#)



### S

- `sphinx_ros`, 9
- `sphinx_ros.directives`, 10
- `sphinx_ros.domain`, 9
- `sphinx_ros.indices`, 9
- `sphinx_ros.xref_role`, 11



**S**

sphinx\_ros\_example, 5



---

## Message Type Index

---

### f

Foo (in sphinx\_ros\_example), 6





## A

`add_object_to_domain_data()`  
     (*sphinx\_ros.directives.RosObject*      *method*),  
     10

`add_package()`      (*sphinx\_ros.domain.RosDomain*  
     *method*), 9

## B

`Bar` (*service in package sphinx\_ros\_example*), 6

## C

configuration value  
     `ros_add_package_names`, 3  
     `ros_msg_reference_version`, 3

## F

`find_obj()` (*sphinx\_ros.domain.RosDomain* *method*),  
     9

`Foo` (*message in package sphinx\_ros\_example*), 6

`FooBar` (*action in package sphinx\_ros\_example*), 6

## G

`get_index_text()` (*sphinx\_ros.directives.RosObject*  
     *method*), 10

`get_object_type_prefix()`  
     (*sphinx\_ros.directives.RosObject*      *method*),  
     10

`get_signature_prefix()`  
     (*sphinx\_ros.directives.RosObject*      *method*),  
     10

## H

`handle_signature()`  
     (*sphinx\_ros.directives.RosObject*      *method*),  
     10

## R

`ros:act` (*role*), 5

`ros:action` (*directive*), 4

`ros:currentpackage` (*directive*), 4

`ros:message` (*directive*), 4

`ros:msg` (*role*), 4

`ros:package` (*directive*), 3

`ros:pkg` (*role*), 4

`ros:service` (*directive*), 4

`ros:srv` (*role*), 5

`ros_add_package_names`  
     configuration value, 3

`ros_msg_reference_version`  
     configuration value, 3

`RosActionDirective`      (*class*      *in*  
     *sphinx\_ros.directives*), 10

`RosCurrentPackageDirective`      (*class*      *in*  
     *sphinx\_ros.directives*), 10

`RosDomain` (*class in sphinx\_ros.domain*), 9

`RosMessageDirective`      (*class*      *in*  
     *sphinx\_ros.directives*), 10

`RosMessageIndex` (*class in sphinx\_ros.indices*), 10

`RosObject` (*class in sphinx\_ros.directives*), 10

`RosPackageDirective`      (*class*      *in*  
     *sphinx\_ros.directives*), 10

`RosPackageIndex` (*class in sphinx\_ros.indices*), 10

`RosServiceDirective`      (*class*      *in*  
     *sphinx\_ros.directives*), 10

`RosType` (*class in sphinx\_ros.directives*), 11

## S

`setup()` (*in module sphinx\_ros*), 9

`sphinx_ros` (*module*), 9

`sphinx_ros.directives` (*module*), 10

`sphinx_ros.domain` (*module*), 9

`sphinx_ros.indices` (*module*), 9

`sphinx_ros.xref_role` (*module*), 11

`sphinx_ros_example` (*package*), 5