Robot Programming with Lisp

1. Introduction, Setup

Gayane Kazhoyan

Institute for Artificial Intelligence
Universität Bremen

13th October, 2015

Outline

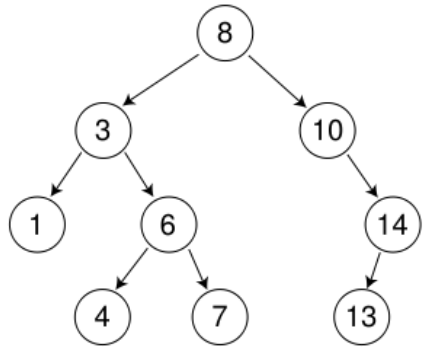
General Info

- Lecturer: Gaya (PhD student at IAI)
- Language: English (and German)
- Correspondence: `gaya@cs.uni-bremen.de` (no StudIP messages please)
- Course number: 03-BE-710.98d
- Credits: 4 ECTS (2 SWS)
- Course type: practical course
- Dates: Tuesdays, 14:15 - 15:45
- Location: TAB Building, Room 2.63 (Bibliothek)

Course content

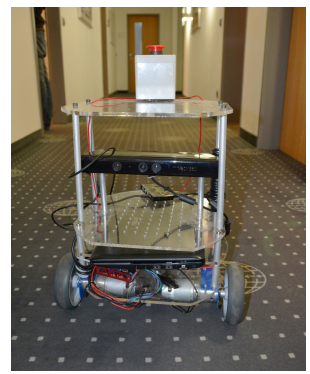
Common Lisp

Artificial Intelligence



Robot Operating System (ROS)

Robot platform



Common Lisp

- Full-featured industry-standard programming language

Common Lisp

- Full-featured industry-standard programming language
- Means for functional programming
- Means for imperative programming
- Means for OOP

Common Lisp

- Full-featured industry-standard programming language
- Means for functional programming
- Means for imperative programming
- Means for OOP
- Fast prototyping through read-eval-print loop and dynamic typing

Common Lisp

- Full-featured industry-standard programming language
- Means for functional programming
- Means for imperative programming
- Means for OOP
- Fast prototyping through read-eval-print loop and dynamic typing
- Compiles into machine code

Common Lisp

- Full-featured industry-standard programming language
- Means for functional programming
- Means for imperative programming
- Means for OOP
- Fast prototyping through read-eval-print loop and dynamic typing
- Compiles into machine code
- Best choice for symbolic processing (AI, theorem proving, etc.)

Common Lisp

- Full-featured industry-standard programming language
- Means for functional programming
- Means for imperative programming
- Means for OOP
- Fast prototyping through read-eval-print loop and dynamic typing
- Compiles into machine code
- Best choice for symbolic processing (AI, theorem proving, etc.)
- Good choice for writing domain-specific programming languages (e.g., robot programming languages)

Common Lisp

- Full-featured industry-standard programming language
- Means for functional programming
- Means for imperative programming
- Means for OOP
- Fast prototyping through read-eval-print loop and dynamic typing
- Compiles into machine code
- Best choice for symbolic processing (AI, theorem proving, etc.)
- Good choice for writing domain-specific programming languages (e.g., robot programming languages)

Applications using / written in dialects of Lisp: Emacs, AutoCAD, Mirai, Google ITA, DART, Maxima, AI and robotics frameworks, ...

ROS

- Middleware for communication of the components of a robotic system

ROS

- Middleware for communication of the components of a robotic system
- Meta-Operating System for programming robotics software (configuring, starting / stopping, logging etc. software components)

ROS

- Middleware for communication of the components of a robotic system
- Meta-Operating System for programming robotics software (configuring, starting / stopping, logging etc. software components)
- Powerful build system (based on CMake), with a strong focus on integration and documentation

ROS

- Middleware for communication of the components of a robotic system
- Meta-Operating System for programming robotics software (configuring, starting / stopping, logging etc. software components)
- Powerful build system (based on CMake), with a strong focus on integration and documentation
- Language-independent architecture (C++, Python, Lisp, Java, JavaScript, ...)

ROS

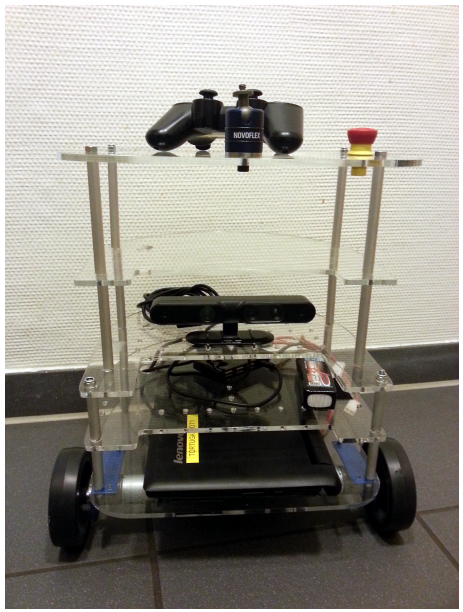
- Middleware for communication of the components of a robotic system
- Meta-Operating System for programming robotics software (configuring, starting / stopping, logging etc. software components)
- Powerful build system (based on CMake), with a strong focus on integration and documentation
- Language-independent architecture (C++, Python, Lisp, Java, JavaScript, ...)
- According to ROS 2014 Community Metrics Report,
  - About 1 million pageviews of `wiki.ros.org` a month
  - About 3.5 million downloads of `.deb` packages a month

ROS

- Middleware for communication of the components of a robotic system
- Meta-Operating System for programming robotics software (configuring, starting / stopping, logging etc. software components)
- Powerful build system (based on CMake), with a strong focus on integration and documentation
- Language-independent architecture (C++, Python, Lisp, Java, JavaScript, ...)
- According to ROS 2014 Community Metrics Report,
  - About 1 million pageviews of `wiki.ros.org` a month
  - About 3.5 million downloads of `.deb` packages a month
- *De facto* standard in modern robotics

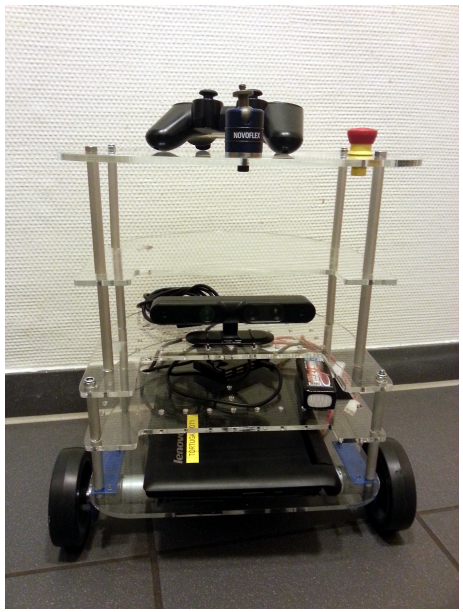
TortugaBot

- 2 controllable wheels



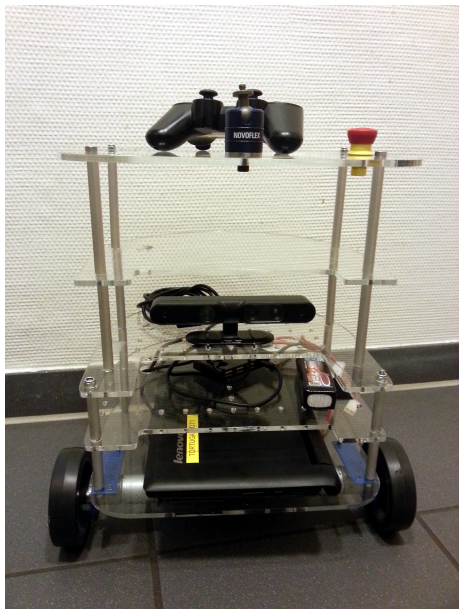
TortugaBot

- 2 controllable wheels
- 2.5D vision sensor



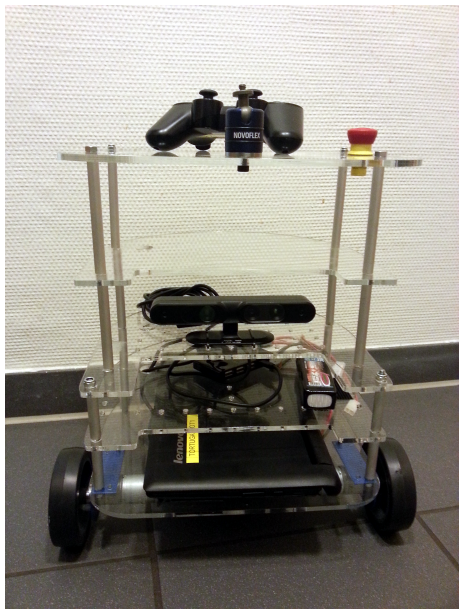
TortugaBot

- 2 controllable wheels
- 2.5D vision sensor
- Asus Eee PC with bluetooth



TortugaBot

- 2 controllable wheels
- 2.5D vision sensor
- Asus Eee PC with bluetooth
- Optional basket in the top part



Why Lisp for robots?

- ROS supports a number of languages: C++, Python, Lisp and Java

Why Lisp for robots?

- ROS supports a number of languages: C++, Python, Lisp and Java
- Lisp is good for rapid prototyping

Why Lisp for robots?

- ROS supports a number of languages: C++, Python, Lisp and Java
- Lisp is good for rapid prototyping
- It is more suitable for symbolic reasoning and AI

Why Lisp for robots?

- ROS supports a number of languages: C++, Python, Lisp and Java
- Lisp is good for rapid prototyping
- It is more suitable for symbolic reasoning and AI
- There are existing robot programming languages in Lisp that automate decision making

Rough schedule

- Introduction, Setup

- Lisp basics
- Functional programming
- OOP

- ROS, ROS Lisp API (*roslisp*)
- *roslisp*, 2D world of *turtlesim*
- coordinate frames, *tf*

- TortugaBot, navigation
- Collision avoidance
- Project scenario

- Project
- *Lab visit*, project
- The big day: competition

Software requirements

Bringing a *personal laptop* is encouraged.

OS:	Ubuntu 14.04 LTS (other Ubuntu versions might work but with no guarantee)
IDE:	Emacs 24
Version control:	Git
Packaging system:	ROS
Lisp software:	SBCL compiler, ASDF build system, Emacs plugin for Common Lisp

Homework assignments and the project

- Homework assignments will mostly consist of filling in the missing gaps in the already existing code.

Homework assignments and the project

- Homework assignments will mostly consist of filling in the missing gaps in the already existing code.
- That code will be hosted on GitHub (`https://github.com`).

Homework assignments and the project

- Homework assignments will mostly consist of filling in the missing gaps in the already existing code.
- That code will be hosted on GitHub (`https://github.com`).
- The code you write should be uploaded to GitHub as well.

Homework assignments and the project

- Homework assignments will mostly consist of filling in the missing gaps in the already existing code.
- That code will be hosted on GitHub (`https://github.com`).
- The code you write should be uploaded to GitHub as well.

- Course final grade = 50 points homework + 50 points group project.

Homework assignments and the project

- Homework assignments will mostly consist of filling in the missing gaps in the already existing code.
- That code will be hosted on GitHub (`https://github.com`).
- The code you write should be uploaded to GitHub as well.

- Course final grade = 50 points homework + 50 points group project.
- To participate in the project you need at least 20 points from the homeworks, otherwise it's a fail.

Homework assignments and the project

- Homework assignments will mostly consist of filling in the missing gaps in the already existing code.
- That code will be hosted on GitHub (`https://github.com`).
- The code you write should be uploaded to GitHub as well.

- Course final grade = 50 points homework + 50 points group project.
- To participate in the project you need at least 20 points from the homeworks, otherwise it's a fail.
- Final grade: 50 points - 4.0, 100 points - 1.0

Homework assignments and the project

- Homework assignments will mostly consist of filling in the missing gaps in the already existing code.
- That code will be hosted on GitHub (`https://github.com`).
- The code you write should be uploaded to GitHub as well.

- Course final grade = 50 points homework + 50 points group project.
- To participate in the project you need at least 20 points from the homeworks, otherwise it's a fail.
- Final grade: 50 points - 4.0, 100 points - 1.0
- Bonus points for very good homework solutions

Bottom line

You will learn / improve your skills in the following:

- Linux
- Git
- Emacs
- Functional programming
- Common Lisp, of course
- ROS (for future roboticists)

...and get to play with a real little robot!

Outline

Assignment goals

Set up your working environment

Set up your GitHub account

Get comfortable with Emacs

Task 1: Install Ubuntu 14.04

- Find out your processor architecture (32 vs. 64 bit).
  Hint: unless your computer is very old, it's most likely 64 bit.
  In Windows 8-, holding the `Windows Key` press `R`, type `dxdiag`, press `Enter` and find the info you need.

Task 1: Install Ubuntu 14.04

- Find out your processor architecture (32 vs. 64 bit).
  Hint: unless your computer is very old, it's most likely 64 bit.
  In Windows 8-, holding the `Windows Key` press `R`, type `dxdiag`, press `Enter` and find the info you need.
- Download Ubuntu 14.04 installation `.iso`:
  `http://www.ubuntu.com/download/desktop`

Task 1: Install Ubuntu 14.04

- Find out your processor architecture (32 vs. 64 bit).
  Hint: unless your computer is very old, it's most likely 64 bit.
  In Windows 8-, holding the `Windows Key` press `R`, type `dxdiag`, press `Enter` and find the info you need.
- Download Ubuntu 14.04 installation `.iso`:
  `http://www.ubuntu.com/download/desktop`
- Burn the `.iso` onto a DVD or create a boot USB.
  Hint: for a bootable USB, in Windows use the Universal USB installer:
  `http://www.pendrivelinux.com/universal-usb-installer-easy-as-1-2-3/`;
  and in Linux you could, e.g., use the `unetbootin`.

Task 1: Install Ubuntu 14.04

- Find out your processor architecture (32 vs. 64 bit).
  Hint: unless your computer is very old, it's most likely 64 bit.
  In Windows 8-, holding the `Windows Key` press `R`, type `dxdiag`, press `Enter` and find the info you need.
- Download Ubuntu 14.04 installation `.iso`:
  `http://www.ubuntu.com/download/desktop`
- Burn the `.iso` onto a DVD or create a boot USB.
  Hint: for a bootable USB, in Windows use the Universal USB installer:
  `http://www.pendrivelinux.com/universal-usb-installer-easy-as-1-2-3/`;
  and in Linux you could, e.g., use the `unetbootin`.
- Install Ubuntu 14.04 (aka Trusty).
  Dual boot installation with default settings is a one click thing.

Task 1: Install Ubuntu 14.04: FAQ

- *How do I boot from CD?*
  You should enter either “Boot Menu” or “BIOS Menu” during reboot
  `https://www.desertcrystal.com/bootkeys`

Task 1: Install Ubuntu 14.04: FAQ

- *How do I boot from CD?*
  You should enter either "Boot Menu" or "BIOS Menu" during reboot
  `https://www.desertcrystal.com/bootkeys`
- *Windows 8+ doesn't let me into "BIOS Menu"!*
  You should restart into the "Boot Options Menu" of your Windows:
  hold down "Shift" while pressing "Restart".
  `http://www.makeuseof.com/tag/how-to-access-the-bios-on-a-windows-8-computer/`

Task 1: Install Ubuntu 14.04: FAQ

- *How do I boot from CD?*
  You should enter either "Boot Menu" or "BIOS Menu" during reboot
  `https://www.desertcrystal.com/bootkeys`
- *Windows 8+ doesn't let me into "BIOS Menu"!*
  You should restart into the "Boot Options Menu" of your Windows:
  hold down "Shift" while pressing "Restart".
  `http://www.makeuseof.com/tag/how-to-access-the-bios-on-a-windows-8-computer/`
- *My BIOS supports UEFI, Ubuntu won't install!*
  Turn off the UEFI mode:
  restart into the "Boot Options Menu" of your Windows,
  choose "Troubleshoot", then "UEFI Firmware Settings"
  `http://www.makeuseof.com/tag/how-to-access-the-bios-on-a-windows-8-computer/`

Task 1: Install Ubuntu 14.04: FAQ

- *How do I boot from CD?*
  You should enter either "Boot Menu" or "BIOS Menu" during reboot
  `https://www.desertcrystal.com/bootkeys`
- *Windows 8+ doesn't let me into "BIOS Menu"!*
  You should restart into the "Boot Options Menu" of your Windows:
  hold down "Shift" while pressing "Restart".
  `http://www.makeuseof.com/tag/how-to-access-the-bios-on-a-windows-8-computer/`
- *My BIOS supports UEFI, Ubuntu won't install!*
  Turn off the UEFI mode:
  restart into the "Boot Options Menu" of your Windows,
  choose "Troubleshoot", then "UEFI Firmware Settings"
  `http://www.makeuseof.com/tag/how-to-access-the-bios-on-a-windows-8-computer/`
- *It still doesn't work!*
  Write an email to `gaya@cs.uni-bremen.de`

Task 2: Install ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal (*hint*: to open a fresh terminal press `<Ctrl>+<Alt>+t`):

- Add ROS repositories to your sources list:

```
sudo sh -c 'echo "deb http://packages.ros.org/ros/ubuntu trusty main" > /etc/apt/sources.list.d/ros-latest.list'
```

Task 2: Install ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal (*hint*: to open a fresh terminal press `<Ctrl>+<Alt>+t`):

- Add ROS repositories to your sources list:

```
sudo sh -c 'echo "deb http://packages.ros.org/ros/ubuntu trusty main" > /etc/apt/sources.list.d/ros-latest.list'
```

- Add their key to your trusted public keys:

```
sudo apt-key adv --keyserver hkp://pool.sks-keyservers.net --recv-key 0xB01FA116
```

Task 2: Install ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal (*hint*: to open a fresh terminal press <Ctrl>+<Alt>+t):

- Add ROS repositories to your sources list:

```
sudo sh -c 'echo "deb http://packages.ros.org/ros/ubuntu trusty main" > /etc/apt/sources.list.d/ros-latest.list'
```

- Add their key to your trusted public keys:

```
sudo apt-key adv --keyserver hkp://pool.sks-keyservers.net --recv-key 0xB01FA116
```

- Update your Debian package index:

```
sudo apt-get update
```

Task 2: Install ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal (*hint*: to open a fresh terminal press <Ctrl>+<Alt>+t):

- Add ROS repositories to your sources list:
  ```
  sudo sh -c 'echo "deb http://packages.ros.org/ros/ubuntu trusty main" > /etc/apt/sources.list.d/ros-latest.list'
  ```
- Add their key to your trusted public keys:
  ```
  sudo apt-key adv --keyserver hkp://pool.sks-keyservers.net --recv-key 0xB01FA116
  ```
- Update your Debian package index:
  ```
  sudo apt-get update
  ```
- The version of ROS distributed with Ubuntu 14.04 is **ROS Indigo**. Install the **desktop** package. Say <No> if asked about `hddtemp`.
  ```
  sudo apt-get install ros-indigo-desktop
  ```

Task 2: Install ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal (*hint*: to open a fresh terminal press <Ctrl>+<Alt>+t):

- Add ROS repositories to your sources list:
  ```
  sudo sh -c 'echo "deb http://packages.ros.org/ros/ubuntu trusty main" > /etc/apt/sources.list.d/ros-latest.list'
  ```
- Add their key to your trusted public keys:
  ```
  sudo apt-key adv --keyserver hkp://pool.sks-keyservers.net --recv-key 0xB01FA116
  ```
- Update your Debian package index:
  ```
  sudo apt-get update
  ```
- The version of ROS distributed with Ubuntu 14.04 is **ROS Indigo**. Install the **desktop** package. Say <No> if asked about `hddtemp`.
  ```
  sudo apt-get install ros-indigo-desktop
  ```
- Install the workspace management tools:
  ```
  sudo apt-get install python-rosinstall && sudo apt-get install python-wstool
  ```

Task 3: Setup ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal:

- Setup rosdep:

```
sudo rosdep init && rosdep update
```

Task 3: Setup ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal:

- Setup rosdep:

  ```
  sudo rosdep init && rosdep update
  ```

- Initialize the ROS environment for this particular terminal:

  ```
  source /opt/ros/indigo/setup.bash
  ```

Task 3: Setup ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal:

- Setup rosdep:
  ```
  sudo rosdep init && rosdep update
  ```
- Initialize the ROS environment for this particular terminal:
  ```
  source /opt/ros/indigo/setup.bash
  ```
- Create a directory where the code you'll write will be stored (the name `ros_ws` and the location ~ can be changed):
  ```
  mkdir -p ~/ros_ws/src
  ```

Task 3: Setup ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal:

- Setup rosdep:
  ```
  sudo rosdep init && rosdep update
  ```
- Initialize the ROS environment for this particular terminal:
  ```
  source /opt/ros/indigo/setup.bash
  ```
- Create a directory where the code you'll write will be stored (the name `ros_ws` and the location ~ can be changed):
  ```
  mkdir -p ~/ros_ws/src
  ```
- Initialize the workspace:
  ```
  cd ~/ros_ws && catkin_make
  ```

Task 3: Setup ROS

Consult the official installation instructions for troubleshooting:
`http://wiki.ros.org/indigo/Installation/Ubuntu`

In short, it boils down to executing the following in the terminal:

- Setup rosdep:
  ```
  sudo rosdep init && rosdep update
  ```
- Initialize the ROS environment for this particular terminal:
  ```
  source /opt/ros/indigo/setup.bash
  ```
- Create a directory where the code you'll write will be stored (the name `ros_ws` and the location ~ can be changed):
  ```
  mkdir -p ~/ros_ws/src
  ```
- Initialize the workspace:
  ```
  cd ~/ros_ws && catkin_make
  ```
- Update your bash startup script and make sure it worked:
  ```
  echo -e "\n# ROS\nsource $HOME/ros_ws/devel/setup.bash\n" >> ~/.bashrc && tail ~/.bashrc && source ~/.bashrc
  ```

Task 4: Git and GitHub

- Create an account on GitHub if you don't have one yet and request a private repository student discount for it (use an Uni Bremen email):

  `https://github.com/join` `https://education.github.com/discount_requests/new`

Task 4: Git and GitHub

- Create an account on GitHub if you don't have one yet and request a private repository student discount for it (use an Uni Bremen email):

  `https://github.com/join` `https://education.github.com/discount_requests/new`

- Create a new empty repository called `lisp_course_material` in your GitHub account and make it private once possible.

Task 4: Git and GitHub

- Create an account on GitHub if you don't have one yet and request a private repository student discount for it (use an Uni Bremen email):

  `https://github.com/join` `https://education.github.com/discount_requests/new`

- Create a new empty repository called `lisp_course_material` in your GitHub account and make it private once possible.
- Add `gaya-` (mind the dash!) as a collaborator to that repo.

Task 4: Git and GitHub

- Create an account on GitHub if you don't have one yet and request a private repository student discount for it (use an Uni Bremen email):

  `https://github.com/join` `https://education.github.com/discount_requests/new`

- Create a new empty repository called `lisp_course_material` in your GitHub account and make it private once possible.
- Add `gaya-` (mind the dash!) as a collaborator to that repo.
- Install Git:

  ```
  sudo apt-get install git
  ```

Task 4: Git and GitHub

- Create an account on GitHub if you don't have one yet and request a private repository student discount for it (use an Uni Bremen email):

  `https://github.com/join` `https://education.github.com/discount_requests/new`

- Create a new empty repository called `lisp_course_material` in your GitHub account and make it private once possible.
- Add `gaya-` (mind the dash!) as a collaborator to that repo.
- Install Git:

  ```
  sudo apt-get install git
  ```

- Download the course material into your ROS workspace:

  ```
  roscd && cd ../src && git clone https://github.com/code-iai/lisp_course_material.git && ll
  ```

Task 4: Git and GitHub

- Create an account on GitHub if you don't have one yet and request a private repository student discount for it (use an Uni Bremen email):

  `https://github.com/join` `https://education.github.com/discount_requests/new`

- Create a new empty repository called `lisp_course_material` in your GitHub account and make it private once possible.
- Add `gaya-` (mind the dash!) as a collaborator to that repo.
- Install Git:

  ```
  sudo apt-get install git
  ```

- Download the course material into your ROS workspace:

  ```
  roscd && cd ../src && git clone https://github.com/code-iai/lisp_course_material.git && ll
  ```

- Define a remote target with the address of your new GitHub repo:

  ```
  cd lisp_course_material && git remote add my-repo https://github.com/YOUR_GITHUB_USERNAME/lisp_course_material.git
  ```

Task 4: Git and GitHub

- Create an account on GitHub if you don't have one yet and request a private repository student discount for it (use an Uni Bremen email):

  `https://github.com/join` `https://education.github.com/discount_requests/new`

- Create a new empty repository called `lisp_course_material` in your GitHub account and make it private once possible.
- Add `gaya-` (mind the dash!) as a collaborator to that repo.
- Install Git:

  ```
  sudo apt-get install git
  ```

- Download the course material into your ROS workspace:

  ```
  roscd && cd ../src && git clone https://github.com/code-iai/lisp_course_material.git && ll
  ```

- Define a remote target with the address of your new GitHub repo:

  ```
  cd lisp_course_material && git remote add my-repo https://github.com/YOUR_GITHUB_USERNAME/lisp_course_material.git
  ```

- Upload the files to your new GitHub repo:

  ```
  git push -u my-repo master
  ```

Task 5: Install the IDE

- Install the editor itself (Emacs), the Common Lisp compiler (SBCL), the linker (ASDF) and the Emacs Common Lisp plugin (Slime):

```
sudo apt-get install ros-indigo-roslisp-repl
```

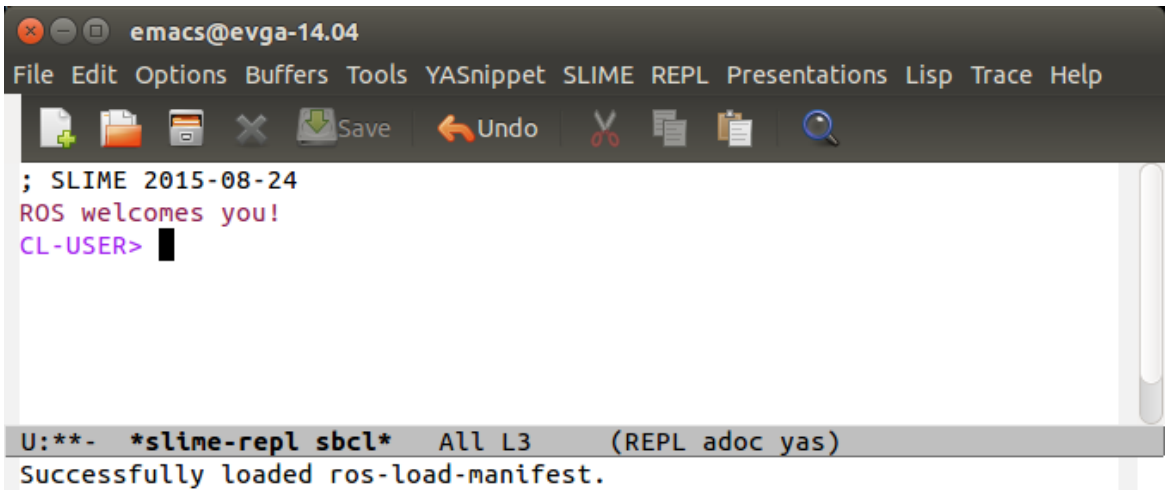
Task 5: Install the IDE

- Install the editor itself (Emacs), the Common Lisp compiler (SBCL), the linker (ASDF) and the Emacs Common Lisp plugin (Slime):

```
sudo apt-get install ros-indigo-roslisp-repl
```

- Start the editor (after compilation is finished you'll see the Lisp shell):

```
roslisp_repl &
```



Task 6: Get familiar with Emacs

The following notation is used in Emacs for keyboard shortcuts:

- `C` for `<Ctrl>`
- `M` for `<Alt>`
- `SPC` for `<Space>`
- `RET` for `<Enter>`
- `-` for when two keys are pressed together (e.g. `C-x` for `<Ctrl>+x`)

The basic shortcuts you will need are listed below:

- `C-x C-f` opens a file
- `C-x 3` or `C-x 2` opens a new tab, `C-x 0` closes it, `C-x 1` maximizes
- `C-x o` switches between tabs
- `C-x b` switches buffers, `C-x C-b` lists all open buffers, `C-x k` kills
- `C-g` cancels a command half-way, `C-x C-c yes` exits Emacs

Task 6: Get familiar with Emacs

The following notation is used in Emacs for keyboard shortcuts:

- `C` for `<Ctrl>`
- `M` for `<Alt>`
- `SPC` for `<Space>`
- `RET` for `<Enter>`
- `-` for when two keys are pressed together (e.g. `C-x` for `<Ctrl>+x`)

The basic shortcuts you will need are listed below:

- `C-x C-f` opens a file
- `C-x 3` or `C-x 2` opens a new tab, `C-x 0` closes it, `C-x 1` maximizes
- `C-x o` switches between tabs
- `C-x b` switches buffers, `C-x C-b` lists all open buffers, `C-x k` kills
- `C-g` cancels a command half-way, `C-x C-c yes` exits Emacs

Open the file with your first assignment and follow the instructions:

```
ROS_WORKSPACE/src/lisp_course_material/assignment_1/src/orc-battle.lisp
```

Task 7: Get familiar with Git

- Once done editing `orc-battle.lisp`, setup colorful output for Git and check what's new in your local repo (the one on your hard drive):

```
git config --global color.ui true && cd ROS_WORKSPACE/src/lisp_course_material && git status
```

Task 7: Get familiar with Git

- Once done editing `orc-battle.lisp`, setup colorful output for Git and check what's new in your local repo (the one on your hard drive):

```
git config --global color.ui true && cd ROS_WORKSPACE/src/lisp_course_material && git status
```

- To see which exactly lines changed ask for the `diff` (*q* to exit):

```
git diff
```

Task 7: Get familiar with Git

- Once done editing `orc-battle.lisp`, setup colorful output for Git and check what's new in your local repo (the one on your hard drive):

```
git config --global color.ui true && cd ROS_WORKSPACE/src/lisp_course_material && git status
```

- To see which exactly lines changed ask for the `diff` (*q* to exit):

```
git diff
```

- The red files are the new untracked ones, the green ones are already in the Git index. To add new files to the index use

```
git add .
```

Task 7: Get familiar with Git

- Once done editing `orc-battle.lisp`, setup colorful output for Git and check what's new in your local repo (the one on your hard drive):

```
git config --global color.ui true && cd ROS_WORKSPACE/src/lisp_course_material && git status
```

- To see which exactly lines changed ask for the `diff` (*q* to exit):

```
git diff
```

- The red files are the new untracked ones, the green ones are already in the Git index. To add new files to the index use

```
git add .
```

- If you deleted some files, to remove them from the index use

```
git add -u
```

Task 7: Get familiar with Git

- Once done editing `orc-battle.lisp`, setup colorful output for Git and check what's new in your local repo (the one on your hard drive):

```
git config --global color.ui true && cd ROS_WORKSPACE/src/lisp_course_material && git status
```

- To see which exactly lines changed ask for the `diff` (*q* to exit):

```
git diff
```

- The red files are the new untracked ones, the green ones are already in the Git index. To add new files to the index use

```
git add .
```

- If you deleted some files, to remove them from the index use

```
git add -u
```

- Once you're sure the changes are final, commit locally:

```
git commit -vm "A meaningful commit message."
```

Task 7: Get familiar with Git

- Once done editing `orc-battle.lisp`, setup colorful output for Git and check what's new in your local repo (the one on your hard drive):

```
git config --global color.ui true && cd ROS_WORKSPACE/src/lisp_course_material && git status
```

- To see which exactly lines changed ask for the `diff` (*q* to exit):

```
git diff
```

- The red files are the new untracked ones, the green ones are already in the Git index. To add new files to the index use

```
git add .
```

- If you deleted some files, to remove them from the index use

```
git add -u
```

- Once you're sure the changes are final, commit locally:

```
git commit -vm "A meaningful commit message."
```

- Finally, to upload your local commits to the GitHub server, push the changes upstream:

```
git push # or git push my-repo master
```

Links

- Emacs cheat sheet:

  `http://www.ic.unicamp.br/~helio/disciplinas/MC102/Emacs_Reference_Card.pdf`

- Git reference book:

  `http://git-scm.com/book/de`

Info summary

Assignment:

- Due: 19.10, Monday, 08:00
- Points: 3 of 50
- For questions: write an email to `gaya@cs.uni-bremen.de` or come by at TAB 1.57

Next class:

- Date: 20.10
- Time: 14:15 (14:00 - 14:15 for questions)
- Place: same room (TAB 2.63)

Q & A

Thanks for your attention!