Roles and Responsibilities of Maintainers

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Outline

1 Explain Package Maintainership
   Purpose of a Maintainer
   Role of a Maintainer
   What being a maintainer requires

2 Call for Maintainers
   Maitainer Status Page

3 Bonus: ROS Version Survey Results

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Purpose of a Maintainer

- Provide a package for use by the community.
- Provide a point of contact for the community to keep track of the state of the package.

Role of a Maintainer

Take code released by someone else and package it using Bloom. Specifically:

- Create a git-buildpackage style repository.
- Import the upstream code (from source control, tarball, etc)
- Create the release tags
- Submit a pull request to update the indexed version

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Role of a Maintainer

- Review pull requests and merge them if they are appropriate and pass unit tests..

- Provide responses in the bug tracker even if it's just to say, there's not developer time for this right now.

- It is *not* doing major development, and they should feel fine to push back any patch which is not up to their standard for the submitter to update.

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What being a maintainer requires

Skills:

- Being able to operate a bug tracker
- Merging the occational pull pull request (more generically merge patches)
- Releasing package with bloom. (See bloom tutorials)

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Outline

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Call for Maintainers

Please consider being a maintainer.

- Ensure that packages you rely on are available.
- Become a contributing member of the community.
- It's not a large commitment.
  - Can commit for just one distribution
  - Time requirements:
    - A couple of hours to release for each version of ROS.
    - 10-15 minutes a week to respond to issue trackers and review patches.

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Status Page

`http://ros.org/debbuld/groovy.html`

ros	1.9.45-0	wet	maintained	Dirk Thomas	
mjpeg_server	1.1.0-0	wet	unknown	Russell Toris	
gps_umd	0.1.5	dry	--		
libccd	1.4.0-3	wet	unknown	Ioan Sucan	
tf	1.9.29-0	wet	maintained	Tully Foote	
rqt_publisher	0.2.16-0	wet	developed	Dorian Scholz, Isaac Saito	
ecl_lite	0.50.5-0	wet	unknown	Daniel Stonier	
pr2-desktop	1.0.0	variant	--		
timestamp_tools	1.6.6-0	wet	end-of-life	Chad Rockey	

Current Status

Statistics:

- groovy declared status:
    - 31 maintained
    - 6 developed
    - 5 end-of-life
    - coverage 25%
- hydro declared status:
    - 64 maintained
    - 4 developed
    - 1 end-of-life
    - coverage 45%
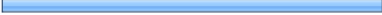
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3. **Bonus: ROS Version Survey Results**

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ROS Version Survey Results
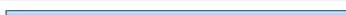
1. What ROS distributions do you actively use?

		Response Percent	Response Count
Boxturtle		0.0%	0
Cturtle		0.0%	0
Diamondback		4.1%	8
Electric		13.8%	27
Fuerte		**70.9%**	**139**
Groovy		52.6%	103
Hydro		3.1%	6
		answered question	196
		skipped question	0

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ROS Version Survey Results

2. What ROS distributions have you used in the past?

	Response Percent	Response Count
Boxturtle	22.6%	44
Cturtle	43.6%	85
Diamondback	70.8%	138
Electric	**80.5%**	**157**
Fuerte	63.6%	124
Groovy	39.0%	76
Hydro	2.1%	4
answered question		195
skipped question		1

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ROS Version Survey Results

3. When do you upgrade to a new ROS distro?

		Response Percent	Response Count
During alpha		0.0%	0
During beta		6.2%	12
After the release		12.8%	25
Within 1 month		3.6%	7
Within 2 months		6.2%	12
Within 3 months		15.9%	31
Within 6 months		**24.1%**	**47**
Before your old distro goes EOL		15.9%	31
Not at all unless you need specific patches		15.4%	30
		answered question	195
		skipped question	1

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ROS Version Survey Results

4. How often would you like to have a new ROS distro (implying new features are released)?		Response Percent	Response Count
3 months		3.1%	6
6 months		23.6%	46
9 months		9.2%	18
12 months		**50.3%**	**98**
15 months		2.1%	4
18 months		7.2%	14
21 months		0.0%	0
24 months		4.6%	9
		answered question	195
		skipped question	1

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ROS Version Survey Results

5. How long would you like to see specific versions of ROS supported (bug fix only)?		Response Percent	Response Count
6 months		3.6%	7
12 months		15.5%	30
18 months		12.9%	25
24 months		**35.6%**	**69**
36 months		20.1%	39
48 months		4.6%	9
60 months		3.1%	6
72 months		4.6%	9
answered question			194
skipped question			2

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ROS Version Survey Results

6. Please state how you agree with these statements.							
	Strongly Disagree	Disagree	Neutral	Agree	Strongly Agree	Rating Average	Rating Count
I favor the release of new features over API stability. (Requiring me to update my code, but getting new versions of libraries)	13.3% (26)	**39.5% (77)**	22.6% (44)	19.0% (37)	5.6% (11)	2.64	195
Comments							26
I would use an LTS version (bug fix only) over the latest ROS distro version.	1.5% (3)	11.3% (22)	17.9% (35)	**38.5% (75)**	30.8% (60)	3.86	195
Comments							26
Except my own code, I build most of the dependent packages myself (from source vs installing from apt).	**42.5% (82)**	37.8% (73)	10.9% (21)	7.3% (14)	1.6% (3)	1.88	193
Comments							14
						Comments	0
						answered question	196
						skipped question	0

ROS Version Survey Results

7. I update my binary packages		Response Percent	Response Count
hourly		0.0%	0
daily		19.4%	38
weekly		**39.8%**	**78**
monthly		14.8%	29
bi monthly		5.1%	10
longer		11.2%	22
don't know		9.7%	19
	answered question		196
	skipped question		0

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Discussion Starter

From these results it seems pretty clear that the community would prefer:

- Change to 12 month release cycle
- Support releases for 24 months

Open questions

- How long to keep Hydro in Beta?
- How to intermesh with Ubuntu release cycle?
- Do we provide a backports/unstable repository?
- Do we split repositories into main and universe?

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Questions

Questions?
This presentation will be ported to the
wiki and posted at:
`http://www.ros.org/wiki/`
`MaintenanceGuide`

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