1. Make sure you added the Create messages and packages (one time thing)
   1. (2 separate commands)
   2. sudo apt install -y ros-humble-irobot-create-msgs
   3. sudo apt install -y build-essential python3-colcon-common-extensions python3-rosdep ros-humble-rmw-cyclonedds-cpp
2. If you have not already, this is a helpful command. This makes it so you don’t have to source ros every time you open a new terminal (one time thing)
   1. echo "source /opt/ros/humble/setup.bash" >> ~/.bashrc
3. Lastly, make sure your middleware is set up (one time thing)
   1. echo "export RMW\_IMPLEMENTATION=rmw\_cyclonedds\_cpp" >> ~/.bashrc
4. If you did any of the above, run this to restart your terminal with the new settings (one time thing):
   1. source ~/.bashrc
5. Lastly, this is a dependency for KeyCommander.py
   1. pip install pynput