

```
yahboom@VM:~/roscourse_ws$ ros2 interface show turtle_interfaces/msg/TurtleMsg
string name
geometry_msgs/Pose turtle_pose
string color
yahboom@VM:~/roscourse_ws$ ros2 interface show turtle_interfaces/srv/SetPose
geometry_msgs/PoseStamped turtle_pose
---
int8 ret
yahboom@VM:~/roscourse_ws$ ros2 interface show turtle_interfaces/srv/SetColor
string color
---
int8 ret
yahboom@VM:~/roscourse_ws$
```

The screenshot shows a Linux desktop with a red background. A notification bubble in the top center reads: ``colcon build` successful` and `/home/yahboom/roscourse_ws`. A terminal window titled `yahboom@VM: ~/roscourse_ws` is open, displaying the output of a `colcon build --symlink-install` command. The terminal shows the ROS version as `ros-foxy` and the domain ID as `66`. The build process for three packages is shown: `turtle_interfaces`, `webcam`, and `python_turtle`. The `webcam` package finished in 4.66s, `turtle_interfaces` in 13.2s, and `python_turtle` in 4.07s. The total time for all three packages is 18.2s.

```
yahboom@VM: ~/roscourse_ws
bash: /home/yahboom/yahboomcar_ros2_ws/yahboomcar_ws/install/setup.bash: No such
file or directory
bash: /home/yahboom/yahboomcar_ros2_ws/software/library_ws/install/setup.bash: N
o such file or directory
-----
ROS VERSION: ros-foxy | ROS_DOMAIN_ID: 66
-----
yahboom@VM:~/roscourse_ws$ colcon build --symlink-install
Starting >>> turtle_interfaces
Starting >>> webcam
Finished <<< webcam [4.66s]
Finished <<< turtle_interfaces [13.2s]
Starting >>> python_turtle
Finished <<< python_turtle [4.07s]
Summary: 3 packages finished [18.2s]
```

