

Assignment 1. Task: “Give your opinion”

Nodes: small independent processes performing computations. They can run at the same time and are able to communicate with each other.

ROScore: collection of nodes and programs. It facilitates the communication of the nodes.

Topics: ROS nodes communicate by sending messages. These messages are named topics.

Services: Services are used for one to one communication between nodes. One node sends information to another node and waits for a response. Information flows on both directions.

Publish/Subscribe: One node that wants to share information will publish a message on the appropriate topic. A node that wants to receive the message will subscribe to this topic.

Catkin_create_pkg: is the command to create a new ROS package. This package will run from the src directory of the workspace. It creates a directory that holds a package, the configuration file (package.xml) and the CMakeLists.txt.

Package.xml: Contains metadata for a package. It defines the name, version, maintainer and dependencies.

Cmake build: building the software packages. The code is built with the catkin_make command. In the catkin workspace the build and devel folders are created. The build folder is where cmake and make are invoked and the devel contains any generated files and targets.