

(1) Compile

(2) Link

copy

declaration

```
// ros/ros.h  
ROS_INFO(string);
```

definition

```
// ros/ros.cpp  
#include <ros/ros.h>  
ROS_INFO(string){  
    cout << string << endl;  
}
```

```
// src/your_code.cpp  
#include <ros/ros.h>  
int main(){  
  
    ROS_INFO("I'm A.");  
  
    return 0;  
}
```

ros.o

your_code.o

executable_file

1. tell **catkin compiler** where is the dependencies
2. add the dependency object to `${catkin_LIBRARIES}`

CMakeLists.txt

```
find_package(catkin REQUIRED  
    Component roscpp  
)
```

```
catkin_package(  
    CATKIN_DEPENDS roscpp  
)
```

```
add_executable(your_node src/your_code.cpp)
```

```
target_link_directories(your_node ${catkin_LIBRARIES})
```