

## ROS Operation Test

1. rosrun turtlesim "double click Tab"
2. rosrun turtlesim turtlesim\_node
3. rosrun turtlesim turtle\_teleop\_key
4. move turtle
5. rqt\_graphros
6. rosnode
7. rosnode list
8. rosnode info /turtlesim
9. rostopic
10. rostopic list
11. rostopic pub /turtle1/cmd\_vel geometry\_msgs/Twist "linear:  
x: 0.0  
y: 0.0  
z: 0.0  
angular:  
x: 0.0  
y: 0.0  
z: 0.0"
12. left/right arrow ◀▶
13. x: 1.0  
y: 0.0  
z: 0.0  
angular:  
x: 0.0  
y: 0.0  
z: 0.0"  
only move once
14. ctrl +c
15. top arrow ▲
16. rostopic pub -r 10 /turtle1/cmd\_vel geometry\_msgs/Twist "linear:  
x: 1.0  
y: 0.0  
z: 0.0  
angular:  
x: 0.0  
y: 0.0  
z: 1.0"  
rotate
17. ctrl +c
18. top arrow ▲
19. x: 1.0  
y: 0.0  
z: 0.0  
angular:  
x: 0.0  
y: 0.0  
z: 1.0"  
rotate
20. ctrl +c
21. rosmmsg show geometry\_msgs/Twist
22. rosservice list
23. rosservice call /spawn "x: 0.0

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y: 0.0
theta: 0.0
name: ' ' '
24. rosservice call /spawn "x: 2.0
y: 2.0
theta: 0.0
name: ' turtle2' "
25. rostopic list
26. rosbag record -a -O cmd_record
27. move turtle
28. ctrl +c
29. rosbag play cmd_record.bag
```