

lab2 package

eater.py /eater_node

Subscribers:

- /goal_pose: geometry_msgs/msg/PoseStamped
- /mouse_position: geometry_msgs/msg/Point
- /turtle1/pizza_count: std_msgs/msg/Int64
- /turtle1/pose: turtlesim/msg/Pose

Publishers:

- /parameter_events: rcl_interfaces/msg/ParameterEvent
- /rosout: rcl_interfaces/msg/Log
- /turtle1/cmd_vel: geometry_msgs/msg/Twist

Service Servers:

- /eater_node/describe_parameters: rcl_interfaces/srv/DescribeParameters
- /eater_node/get_parameter_types: rcl_interfaces/srv/GetParameterTypes
- /eater_node/get_parameters: rcl_interfaces/srv/GetParameters
- /eater_node/list_parameters: rcl_interfaces/srv/ListParameters
- /eater_node/set_parameters: rcl_interfaces/srv/SetParameters
- /eater_node/set_parameters_atomically: rcl_interfaces/srv/SetParametersAtomically

Service Clients:

- /spawn_pizza: turtlesim_plus_interfaces/srv/GivePosition
- /turtle1/eat: std_srvs/srv/Empty

Action Servers:

Action Clients:

killer.py /killer_node

Subscribers:

- /turtle1/pizza_count: std_msgs/msg/Int64
- /turtle1/pose: turtlesim/msg/Pose
- /turtle2/pose: turtlesim/msg/Pose

Publishers:

- /parameter_events: rcl_interfaces/msg/ParameterEvent
- /rosout: rcl_interfaces/msg/Log
- /turtle2/cmd_vel: geometry_msgs/msg/Twist

Service Servers:

- /killer_node/describe_parameters: rcl_interfaces/srv/DescribeParameters
- /killer_node/get_parameter_types: rcl_interfaces/srv/GetParameterTypes
- /killer_node/get_parameters: rcl_interfaces/srv/GetParameters
- /killer_node/list_parameters: rcl_interfaces/srv/ListParameters
- /killer_node/set_parameters: rcl_interfaces/srv/SetParameters
- /killer_node/set_parameters_atomically: rcl_interfaces/srv/SetParametersAtomically

Service Clients:

- /remove_turtle: turtlesim/srv/Kill

Action Servers:

Action Clients:

turtlesim_pose.py /odom_pub

Subscribers:

- /turtle1/pose: turtlesim/msg/Pose
- /turtle2/pose: turtlesim/msg/Pose

Publishers:

- /odom1: nav_msgs/msg/Odometry
- /odom2: nav_msgs/msg/Odometry
- /parameter_events: rcl_interfaces/msg/ParameterEvent
- /rosout: rcl_interfaces/msg/Log
- /tf: tf2_msgs/msg/TFMessage

Service Servers:

- /odom_pub/describe_parameters: rcl_interfaces/srv/DescribeParameters
- /odom_pub/get_parameter_types: rcl_interfaces/srv/GetParameterTypes
- /odom_pub/get_parameters: rcl_interfaces/srv/GetParameters
- /odom_pub/list_parameters: rcl_interfaces/srv/ListParameters
- /odom_pub/set_parameters: rcl_interfaces/srv/SetParameters
- /odom_pub/set_parameters_atomically: rcl_interfaces/srv/SetParametersAtomically

Service Clients:

Action Servers:

Action Clients:

rviz2 /rviz

Subscribers:

- /odom1: nav_msgs/msg/Odometry
- /odom2: nav_msgs/msg/Odometry
- /parameter_events: rcl_interfaces/msg/ParameterEvent

Publishers:

- /click_event: geometry_msgs/msg/PointStamped
- /goal_pose: geometry_msgs/msg/PoseStamped
- /initial_pose: geometry_msgs/msg/PoseWithCovarianceStamped
- /parameter_events: rcl_interfaces/msg/ParameterEvent
- /rosout: rcl_interfaces/msg/Log

Service Servers:

- /rviz2/describe_parameters: rcl_interfaces/srv/DescribeParameters
- /rviz2/get_parameter_types: rcl_interfaces/srv/GetParameterTypes
- /rviz2/get_parameters: rcl_interfaces/srv/GetParameters
- /rviz2/list_parameters: rcl_interfaces/srv/ListParameters
- /rviz2/set_parameters: rcl_interfaces/srv/SetParameters
- /rviz2/set_parameters_atomically: rcl_interfaces/srv/SetParametersAtomically

Service Clients:

Action Servers:

Action Clients:

turtlesim plus package

turtlesim_plus node.py

/turtlesim_plus

Subscribers:

- /turtle1/cmd_vel: geometry_msgs/msg/Twist
- /turtle2/cmd_vel: geometry_msgs/msg/Twist

Publishers:

- /mouse_position: geometry_msgs/msg/Point
- /parameter_events: rcl_interfaces/msg/ParameterEvent
- /rosout: rcl_interfaces/msg/Log
- /turtle1/pizza_count: std_msgs/msg/Int64
- /turtle1/pose: turtlesim/msg/Pose
- /turtle2/pizza_count: std_msgs/msg/Int64
- /turtle2/pose: turtlesim/msg/Pose
- /turtle2/scan: turtlesim_plus_interfaces/msg/ScannerDataArray

Service Servers:

- /remove_turtle: turtlesim/srv/Kill
- /spawn_pizza: turtlesim_plus_interfaces/srv/GivePosition
- /spawn_turtle: turtlesim/srv/Spawn
- /turtle1/eat: std_srvs/srv/Empty
- /turtle1/stop: std_srvs/srv/Empty
- /turtle2/eat: std_srvs/srv/Empty
- /turtle2/stop: std_srvs/srv/Empty
- /turtlesim_plus/describe_parameters: rcl_interfaces/srv/DescribeParameters
- /turtlesim_plus/get_parameter_types: rcl_interfaces/srv/GetParameterTypes
- /turtlesim_plus/get_parameters: rcl_interfaces/srv/GetParameters
- /turtlesim_plus/list_parameters: rcl_interfaces/srv/ListParameters
- /turtlesim_plus/set_parameters: rcl_interfaces/srv/SetParameters
- /turtlesim_plus/set_parameters_atomically: rcl_interfaces/srv/SetParametersAtomically

Service Clients:

Action Servers:

- /turtle1/detect_pizza: turtlesim_plus_interfaces/action/GetData
- /turtle2/detect_pizza: turtlesim_plus_interfaces/action/GetData

Terminal

Publisher

Subscriber

Service Server

Service Client









