

in setting up ros , the ROS_DOMAIN_ID variable is set to 10

in a node , we create multiple subscribers , each of which subscribe to different topics . A single publisher can publish to one topic only , however a node can have many publishers ,each publishing to different topic.

Ros2 node list

Ros2 node info <node_name> : for information abt nodes

ros2 topic list -t # -t : used to know the type of message
to know what is published on a topic : ros2 topic echo

<topic_name>

to know what is the structure of data of a particular message :

ros2 interface show <type of topic >

to view the rate at which data is published to a topic : eg => ros2
topic hz </turtle1/pose>

we can also set the rate at which data shd be published to a topic .

Ros2 param list : for parameters associated with nodes ;

we can get and set the parameters : ros2 param get <node>
<parameter type>

ros2 param set <node> <parameter type> <value to set>

ros2 param dump <node name> : save a file with the values of
parameters set now , for using in future

to use the saved file : ros2 param load <node_name>
<parameter_file>

echo "export ROS_DOMAIN_ID=10" >> ~/.bashrc

i have set the domain id for my ros2 = 10