

**TELEOP NODE**

Subscribers:

Publishers:

Service Servers:

Service Clients:

Action Servers:

Action Clients:

→ /cmd\_vel : geometry\_msgs/msg/Twist

**CONTROLLER NODE**

Subscribers:

Publishers:

Service Servers:

Service Clients:

Action Servers:

Action Clients:

→ /cmd\_vel : geometry\_msgs/msg/Twist

→ /end\_effector : geometry\_msgs/msg/PoseStamped

→ /joint\_states : sensor\_msgs/msg/JointState

→ /robot\_command : lab4\_interfaces/srv/SetMode

**ROBOT STATE NODE**

Subscribers:

Publishers:

Service Servers:

Service Clients:

Action Servers:

Action Clients:

→ /joint\_states : sensor\_msgs/msg/JointState

→ /robot\_description : std\_msgs/msg/String

→ /tf : tf2\_msgs/msg/TFMessage

→ /tf\_static : tf2\_msgs/msg/TFMessage

**SCHEDULER NODE**

Subscribers:

Publishers:

Service Servers:

Service Clients:

Action Servers:

Action Clients:

→ /setmode : lab4\_interfaces/srv/SetMode

→ /random\_server : lab4\_interfaces/srv/Random

→ /robot\_command : lab4\_interfaces/srv/SetMode

**RANDOM NODE**

Subscribers:

Publishers:

Service Servers:

Service Clients:

Action Servers:

Action Clients:

→ /target : geometry\_msgs/msg/PoseStamped

→ /robot\_command : lab4\_interfaces/srv/SetMode

**RVIZ NODE**

Subscribers:

Publishers:

Service Servers:

Service Clients:

Action Servers:

Action Clients:

→ /robot\_description : std\_msgs/msg/String

→ /end\_effector : geometry\_msgs/msg/PoseStamped

→ /target : geometry\_msgs/msg/PoseStamped

→ /workspace\_points : sensor\_msgs/msg/PointCloud2

**WORKSPACE NODE**

Subscribers:

Publishers:

Service Servers:

Service Clients:

Action Servers:

Action Clients:

→ /workspace\_points : sensor\_msgs/msg/PointCloud2