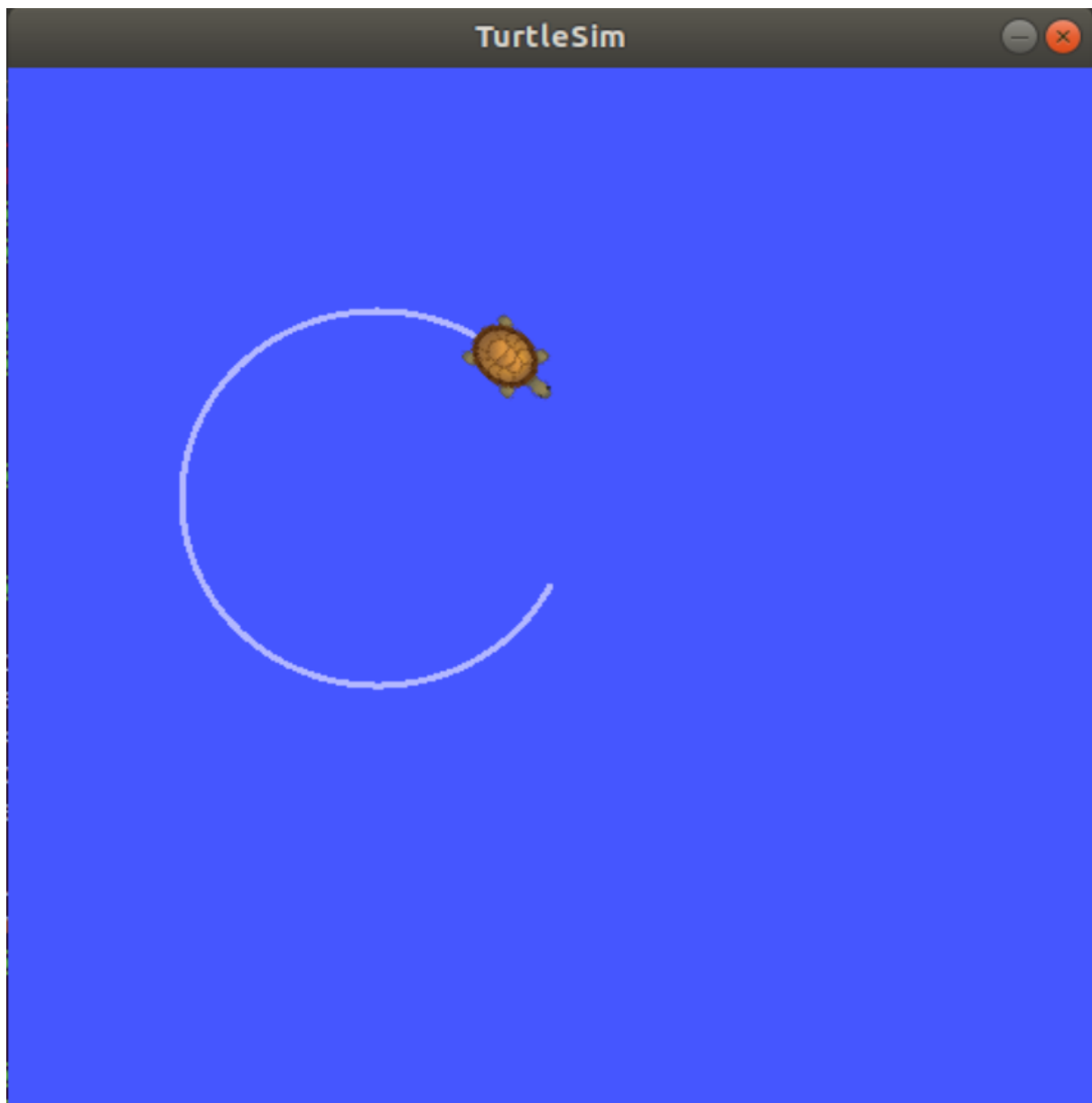


CSE 591: Perception in Robotics

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Title: Project: Intro to ROS

<Screenshot of the turtlesim: First letter of my Last name : C>



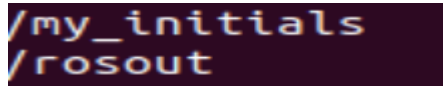
Node:

Short Paragraph for the node I constructed:

Nodes: A node is an executable that uses ROS to communicate with other nodes. Nodes can publish or subscribe to a Topic.

After running the `$ rosnodetop`, I can see the node(/my_initials) what I constructed.

Screenshot:



Also, the `$ rosnodetop` command returns information about a specific node.

Thus, I can get the detail information about the node which is my_initials.

After running `$ rostopic info /my_initials`, this code gives me some more information about my_initials. Specific information should be publications, Subscriptions and Services. Following the information, it publishes /rosout , /turtle1.color_senor and /turtle1/pose. Next, the /turtle1/cmd_vel should be the subscriptions. Also, there are several information in the services. The Pid number is 16081.

Following image is the result from the `$rostopic info /my_initials`

```
Node [/my_initials]
Publications:
* /rosout [roscpp_msgs/Log]
* /turtle1/color_sensor [turtlesim/Color]
* /turtle1/pose [turtlesim/Pose]

Subscriptions:
* /turtle1/cmd_vel [unknown type]

Services:
* /clear
* /kill
* /my_initials/get_loggers
* /my_initials/set_logger_level
* /reset
* /spawn
* /turtle1/set_pen
* /turtle1/teleport_absolute
* /turtle1/teleport_relative

contacting node http://ybcho-VirtualBox:42965/ ...
Pid: 16081
Connections:
* topic: /rosout
  * to: /rosout
  * direction: outbound (47115 - 127.0.0.1:48098) [25]
  * transport: TCPROS
```