



1.3.5

Build your own ROS
application –
define and build
custom message types

Create new sensor type

Don't forget to source your workspace!

```
$ source $HOME/hrwros_ws/devel/setup.bash
```

First, navigate to the folder where ROS message types are defined

```
$ roscd hrwros_msgs  
$ cd msg
```

Then, create the messagefile

```
$ touch SensorInformation.msg
```

You can see all created message types by typing

```
$ rosmmsg show sensor_msgs/Range
```

Create new sensor type

SensorInformation.msg

```
# Example message file

sensor_msgs/Range sensor_data # placeholder for the ROS message
                                type for interfacing with distance
                                sensors

string maker_name              # placeholder for manufacturer
                                name

uint32 part_number             # placeholder for part number of
                                the sensor
```

- Make sure to add the name to the *add_message_files* section in the CMakeLists.txt file.
- Finally, run the catkin build command