Cameron Wolff Lab 1

1. 17 sub-commands; pkg

2. 2 topics; 1 node (/_ros2cli_daemon_0_4ac42baf78354734995dda7928812381)

3. rcl_interfaces/msg/Log; 1 publisher

4. 4 strings; name, msg, file, and function
5. 2 packages; urdf and urdf_parser_plugin

6. apt install ros-humble-turtlesim -y; apt update && apt upgrade ros-humble-turtlesim -y

7. 3 packages

8. Every second, the node prints "publishing: 'Hello World: {i}'", along with the timestamp, node name, and an info label

9. /chatter; std_msgs/msg/String; 1 member variable

10. listener outputs the same info as talker, and the same message prefixed with "I heard"

11.

/talker → /std_msgs/msg/ String /chatter → /listener