

1. Build-in interfaces

- Official documentation
- List the interfaces in the CLI

```
ros2 interface list
```

- Show the details of an interface

```
ros2 interface show <interface>
```

2. Custom interfaces

2.1 Topics

2.2 Services

2.2.1 Set-up

1. Create a new **C++ package** for the interface
 - Only the compilation and package files are needed.
 - If working in a C++ package, creating a new one is **optional**
2. Modify the **compilation** file:
 - In order to convert the interfaces you defined into language-specific code (like C++ and Python) so that they can be used in those languages.
3. Modify the **package** file:
 - Because the interfaces rely on `rosidl_default_generators` for generating language-specific code, you need to declare a dependency on it.
4. Create the **service file**

5. Build the package

2.2 Service file

Official documentation

- Naming: **PascalCase** typography recommended.
- Extension: Has **.srv** extension
- Directory: Stored in its own **srv** folder
- Contents: Based on **std_msgs**. Its general format is:

```
# Request
int64 a
int64 b
---
# Response
int64 c
```

Alternative sources

Robotics back-end