

catkin\_make → compile all packages in a workspace

roscore → start the ROS master

roslaunch <package\_name> <node.py/node.cpp> → run a process/program

roslaunch rqt\_graph rqt\_graph → nodes and topics as graph

rostopic type <topic\_name> → type of the message

roslaunch rqt\_plot rqt\_plot → plotting topic data

rostopic list → list of all nodes

rostopic info <node\_name> → information of a single node

roslaunch ping <node\_name> → check if this node is in another computer and connected to the master

rosservice list → all services

rosservice type <s\_name> → type of the message

rosservice show <service\_type>

rosservice find <service\_type>

roslaunch list

rostopic pub [-1] <topic\_name> <msg\_type> <arguments> → publish a topic once

rosservice call <service> <arguments> → call a service

roslaunch set <param> → change parameter

roslaunch get <param> → retrieve parameter

roslaunch record -a → all topics' readings into a file

roslaunch <package\_name> <xml\_file.launch> → launch several processes in parallel from a single file

