

source /opt/ros/noetic/setup.bash - setting the environment in this source

mkdir -p ~/catkin_ws/src – mldr is to create a workspace inside which source folder is present

cd ~/catkin_ws/ - cd is the command to change directory

catkin_make - convenience tool for building code in a catkin workspace

source devel/setup.bash - this command is used to use your custom roscore

cd src - change directory to source

catkin_create_pkg beginner_tutorials std_msgs rospy roscpp - command is used to create a package

cd ..

catkin_make - convenience tool for building code in a catkin workspace

mkdir scripts - command to create scripts folder

cd scripts - change directory

chmod +x talker.py - chmod +x is the command to make a file executable

gedit - text editor

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chmod +x listener.py - chmod +x is the command to make a file executable

python3 myfirst_node.py

gedit ~/.bashrc - to edit the .bashrc text file

source /opt/ros/noetic/setup.bash - run this command to use your custom roscore

source ~/catkin_ws/devel/setup.bash - run this command to use your custom roscore

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source devel/setup.bash

roslaunch beginner_tutorials sample.launch

roslaunch turtlesim turtlesim_node

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roslaunch turtlesim turtlesim_teleop_key
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rqt_graph
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<https://realitybytes.blog/2018/08/17/graph-based-path-planning-a/amp/>