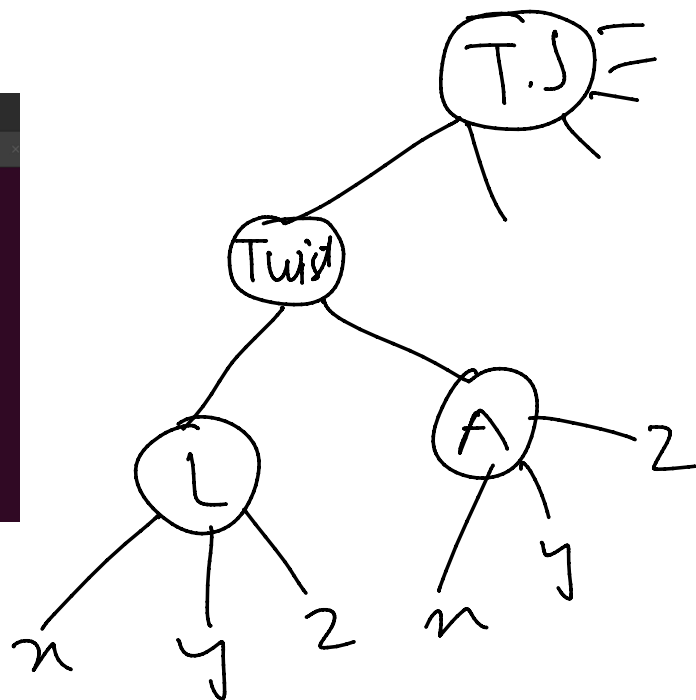


S#2 :: Robot Driving Node

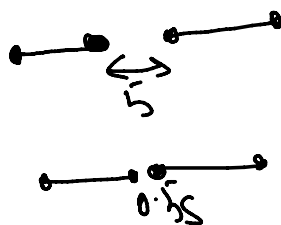
Monday, July 5, 2021 3:36 PM

```
luqman@vtd: ~
luqman@vtd: ~/beginners_ws x luqman@vtd: ~ x luqman@vtd: ~
luqman@vtd:~$ ros2 topic list
/parameter_events
/rosout
/turtle1/cmd_vel
/turtle1/color_sensor
/turtle1/pose
luqman@vtd:~$ ros2 interface show geometry_msgs/msg/Twist
# This expresses velocity in free space broken into its linear and angular parts.
Vector3 linear
Vector3 angular
luqman@vtd:~$ ros2 interface show geometry_msgs/msg/Vector3
# This represents a vector in free space.
# This is semantically different than a point.
# A vector is always anchored at the origin.
# When a transform is applied to a vector, only the rotational component is applied.
float64 x
float64 y
float64 z
luqman@vtd:~$
```



Fast Motion

P/5sec P/0.5s



Slow motion

$\frac{1}{s}$
100/s

s ↓