ROS2 Documentation

⇒ Set of software libraries and tools for building robot applications.

Tutorials

① Configuring your ROS 2 environment

⇒ ROS2 relies on the notion of combining **workspaces** using the shell environment.

- QL is a ROS term for the location on your system where you're developing with ROS 2.
- The core ROS2 workspace is called **underlay**.
- Subsequent local workspace are called **overlay**.

⇒ Combining workspaces makes developing against different versions of ROS2, or against different sets of packages, easier.

⇒ This is accomplished by sourcing setup files every time you open a new shell or by adding the source command to your shell startup script once.

ROS_DOMAIN_ID

- If you have multiple different group of computers running ROS2, and you want to avoide cross-talk between the groups
  - Choose a single integer and set it as the environment variable ROS_DOMAIN_ID on all the computers in a group.
  - Choose different, unique integer for each sub-group.

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→ The integer must be between 0-232 for the ROS2 daemon to successfully start.

→ The domain ID is used to segment the network in order to avoide interferance between different groups of computers running ROS2 on the same local area network.

→ Machines with different domain IDs will not talk, nor interfere, with each other.

```
$ ros2 pkg executables turtlesim
```

↳ Lists out all the nodes in package turtlesim

```
$ ros2 run turtlesim turtlesim_node
```

↳ This will run the node turtlesim_node from package turtlesim