ROS CHEAT SHEET | Knead For Speed

RUNNING NODES

roscore
roslaunch my_package launchfile.launch
rosrun my_package my_node.py

NODES, TOPICS, MESSAGES

rosnode list
rostopic list
rostopic echo joint_commands
rostopic hz joint_commands
rosmsg show geometry_msgs/Twist
roscd my_package

USEFUL TOOLS

These are good for visualizing ROS topics and and relationships between nodes:

rqt
rqt_plot
rqt_graph
rviz

SOMETIPS

Python nodes need to be executable. They should show up as green when you run 1s to list the files in a directory.

Run this to make a file executable:

chmod +x my_file.py

The workspace name is: me212KneadForSpeed

The package names are: delta_robot or mobile_robot

source devel/setup.bash

Needs to be run in every new terminal unless it is in the .bashrc

catkin_make