

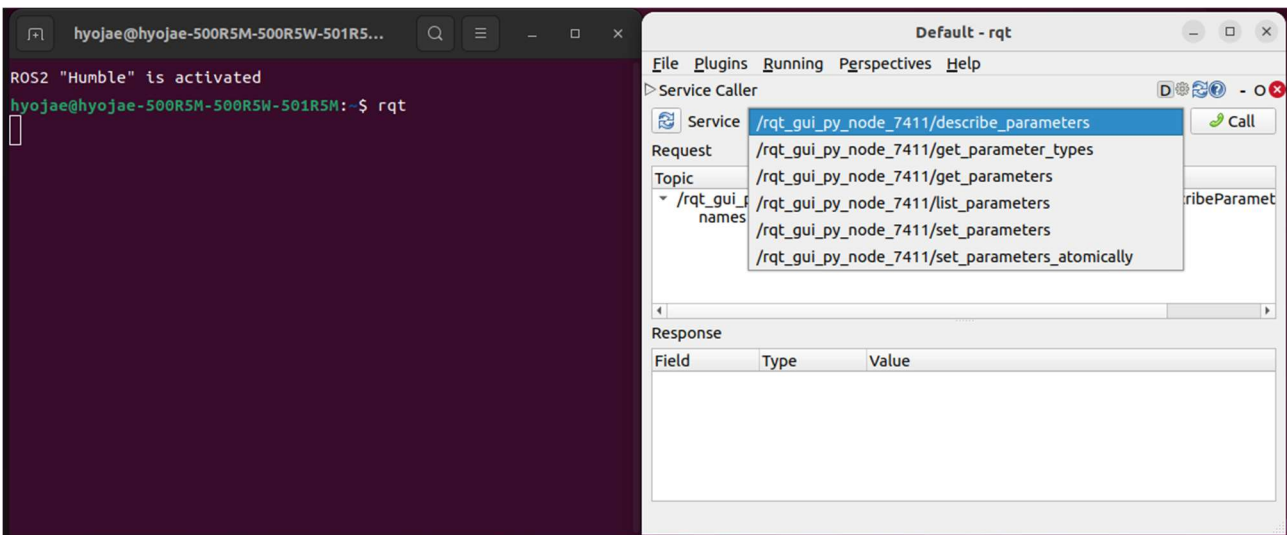
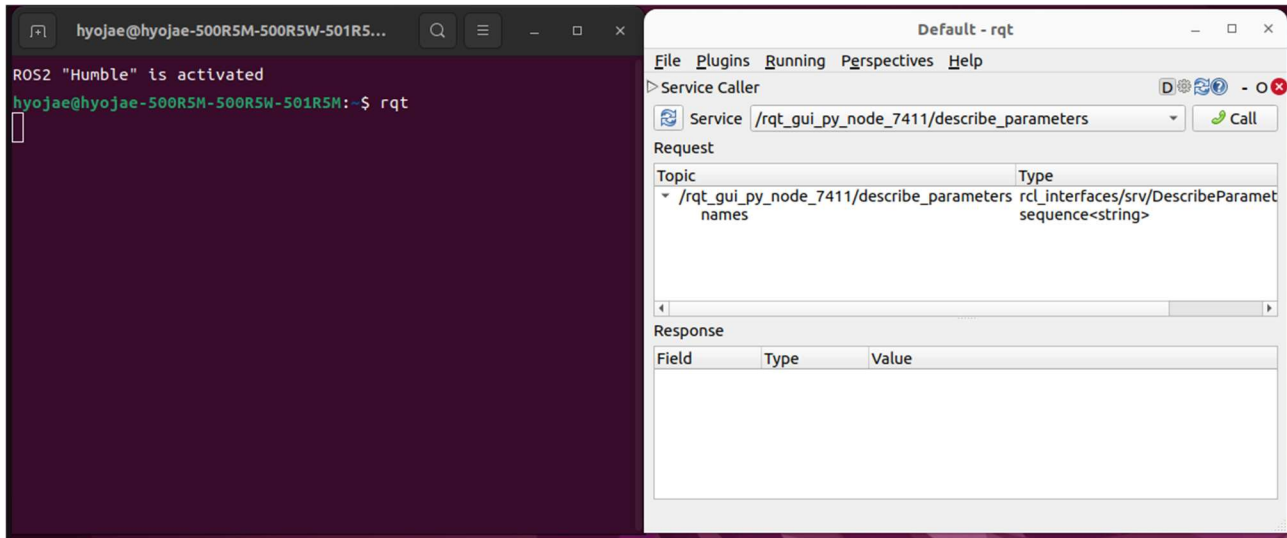
Rqt

설치

`sudo apt install '~nros-humble-rqt*'`

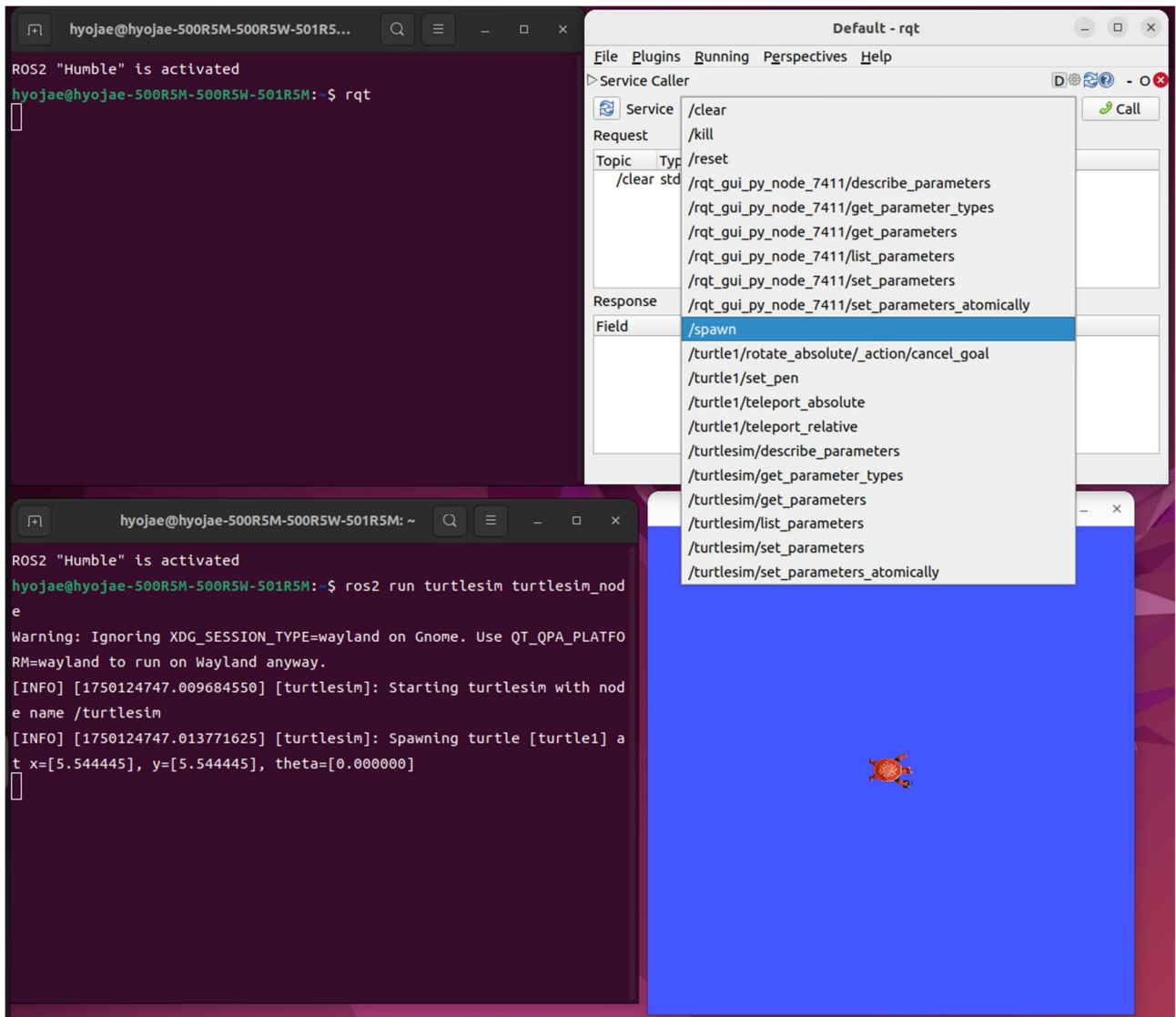
실행

`rqt`



ros2 run turtlesim turtlesim_node

좌측 새로그침 눌러주면 표시됨



Default - rqt

File Plugins Running Perspectives Help

Service Caller

Service: /turtle1/set_pen

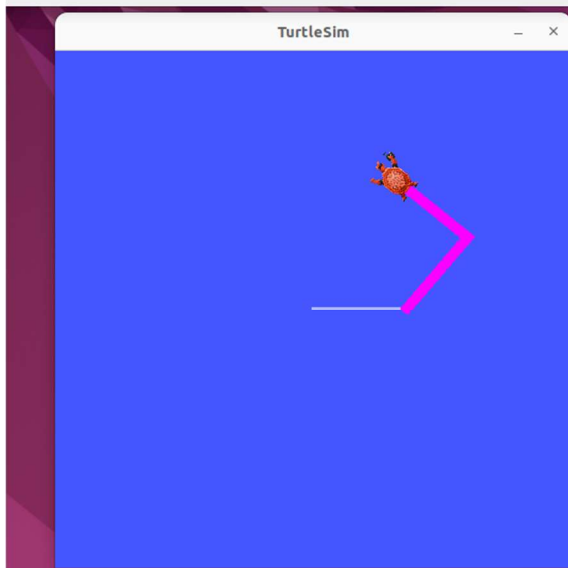
Request

Topic	Type	Expression
/turtle1/set_pen	turtlesim/srv/SetPen	
r	uint8	255
g	uint8	0
b	uint8	255
width	uint8	10
off	uint8	0

Response

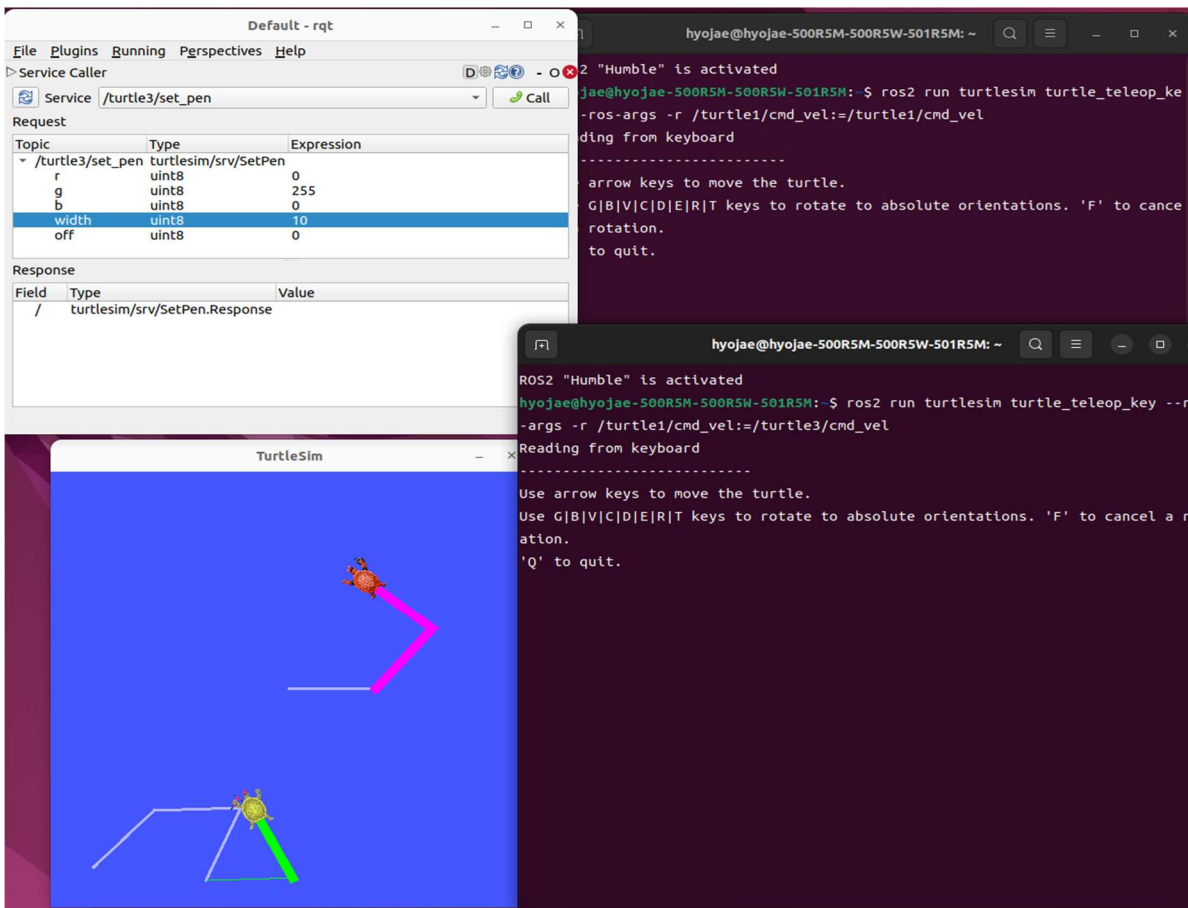
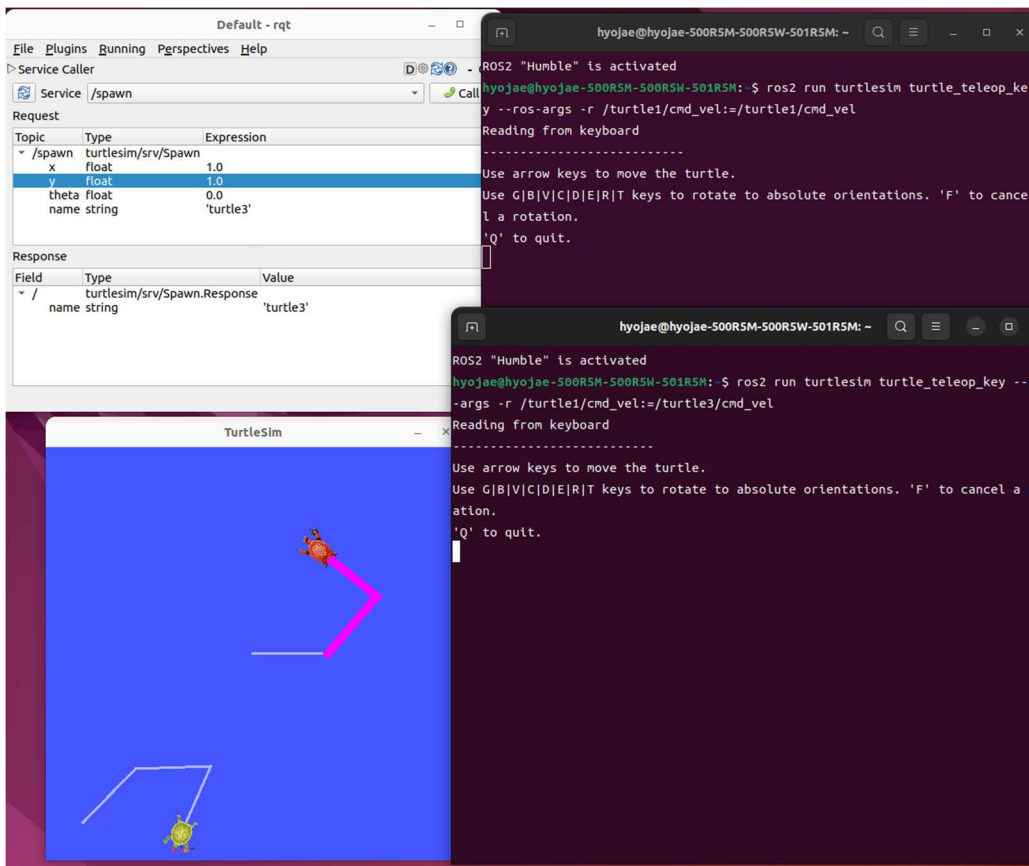
Field	Type	Value
/	turtlesim/srv/SetPen.Response	

```
hyojae@hyojae-500R5M-500R5W-501R5M: ~  
ROS2 "Humble" is activated  
hyojae@hyojae-500R5M-500R5W-501R5M:~$ ros2 run turtlesim turtle_teleop_key  
y --ros-args -r /turtle1/cmd_vel:=/turtle1/cmd_vel  
Reading from keyboard  
-----  
Use arrow keys to move the turtle.  
Use G|B|V|C|D|E|R|T keys to rotate to absolute orientations. 'F' to cancel a rotation.  
'Q' to quit.
```



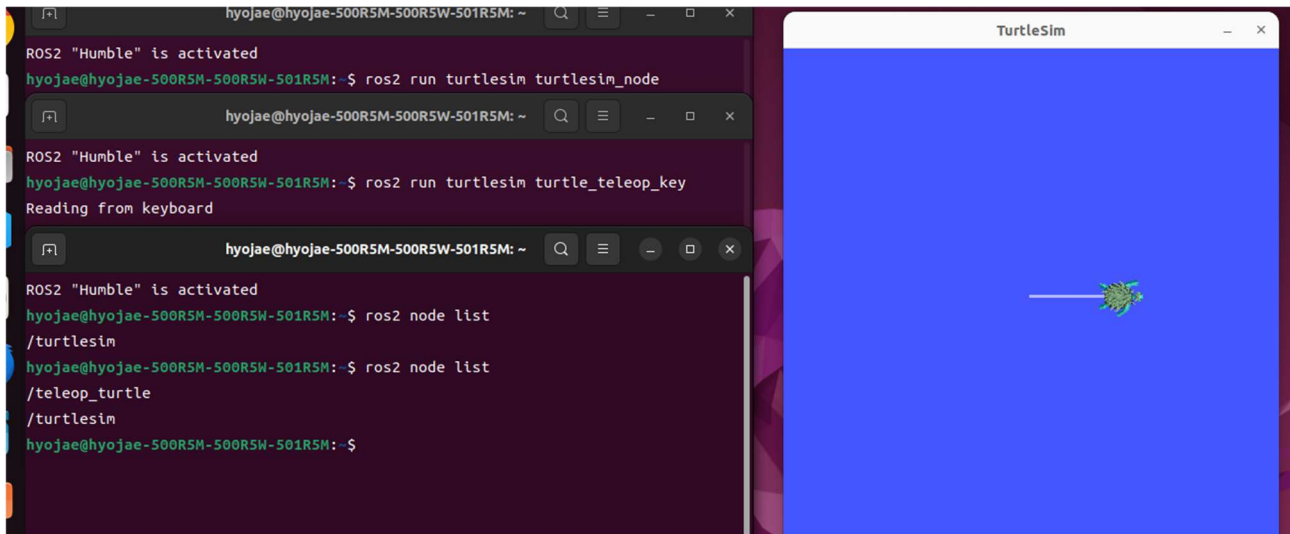
터틀봇 추가 및 이동

ros2 run turtlesim turtle_teleop_key --ros-args -r /turtle1/cmd_vel:=/turtle2/cmd_vel



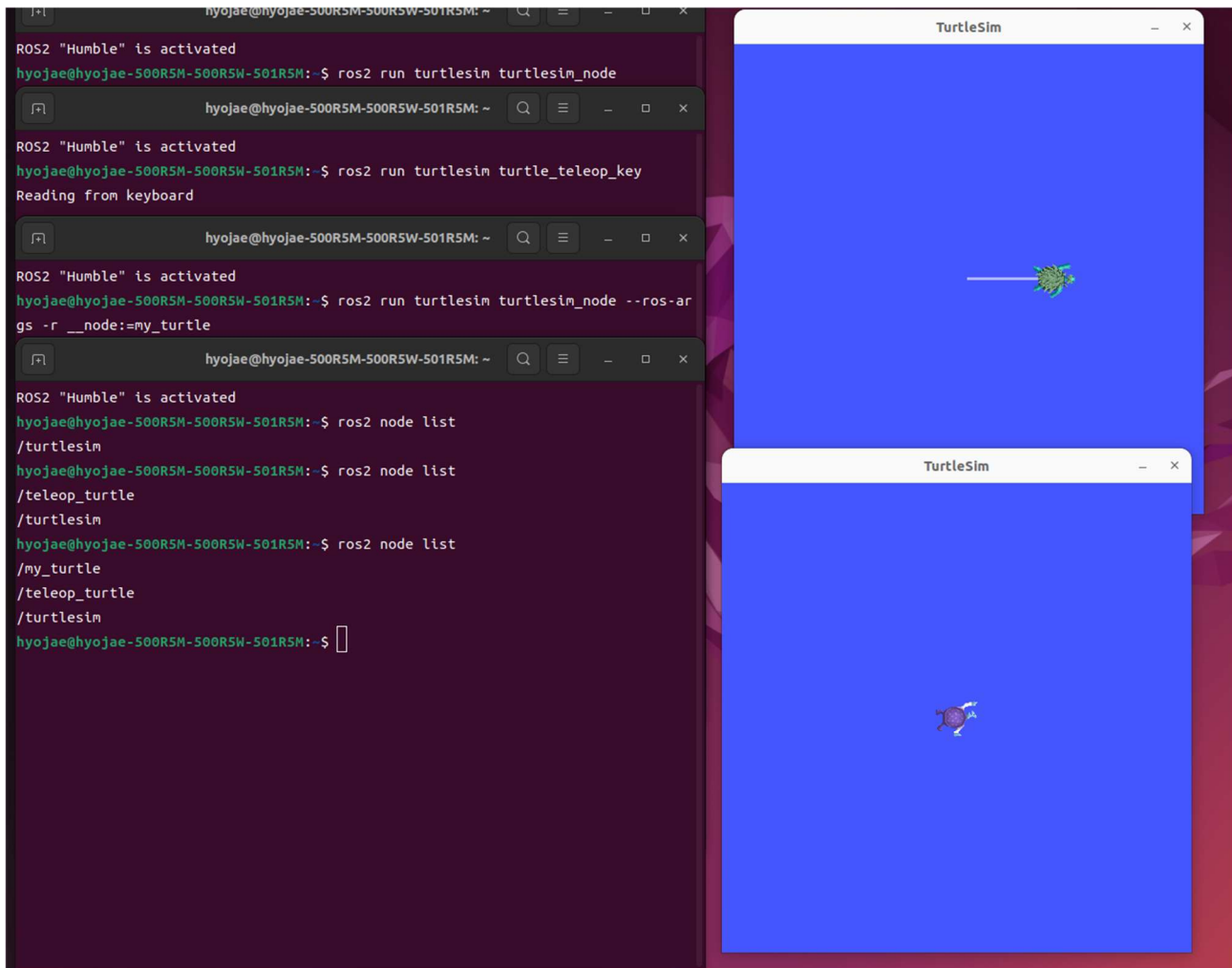
node

ros2 node list



노드 추가

ros2 run turtlesim turtlesim_node --ros-args --remap __node:=my_turtle



이동

