



ROS2

Node

<code>ros2 node list</code>
<code>ros2 node info <node_name></code>
<code>ros2 run <package> <executable></code>

Topics

<code>ros2 topic list</code>
<code>ros2 topic echo <topic></code>
<code>ros2 topic info <topic></code>
<code>ros2 topic pub <topic> <msg_type> "<value>"</code>
<code>ros2 topic info --verbose <topic></code>
<code>ros2 topic pub /cmd_vel geometry_msgs/msg/Twist "{linear: {x: 0.3}, angular: {z: 0.0}}"</code>

Sourcing

<code>source /opt/ros/\$ROS_DISTRO/setup.bash</code>
<code>source install/setup.bash</code>

Colcon (Build Tool)

<code>colcon build</code> → always execute in your workspace folder
<code>colcon build --packages-select <name></code>

Launch

<code>ros2 launch <package> <launch_file></code>
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Interface

<code>ros2 interface list</code>
<code>ros2 interface show <msg_type></code>

Workspace

<code>mkdir -p ros2_ws/src</code>
<code>cd ros2_ws</code>
<code>colcon build</code>
<code>source install/setup.bash</code>

Packages

<code>sudo apt install ros-\$ROS_DISTRO-<package_name></code>
<code>sudo apt install ros-\$ROS_DISTRO-turtle-nest</code>

Tools

<code>rqt</code> → GUI-Toolsammlung
<code>rqt_graph</code> → Graph der Nodes/Topics

Parameter

<code>ros2 param list</code>
<code>ros2 param get <node> <param></code>
<code>ros2 param set <node> <param> <value></code>

Service

<code>ros2 service list</code>
<code>ros2 service type <service></code>
<code>ros2 service call <srv_type> "{...}"</code>

Bags

<code>ros2 bag record <topic_name></code>
<code>ros2 bag record -a</code> – alle Topics aufzeichnen
<code>ros2 bag info <bag_file_name></code>
<code>ros2 bag play <bag_file></code>