ROS Commands and Terminology

* rospack list – list all installed ROS packages
* rospack find <package-name> - find the package-name
* roscd <package-name> – change to this package’s directory (don’t need to be in the parent)
* rosls <package-name> – list the contents of the directory for this package
* roscore – start the ROS master
* node – a running instance of a program is called a node
* rosrun package-name executable-name --- start a node, rosrun doesn’t need a path to the executable; it infers the path to the executable from the package-name
* rosnode list – list all currently running nodes. Note: node names may not match the name of the executable.
* rosnode info – all sorts of useful info about the node
* rqt\_graph – show the communication graph. Ovals represent nodes, arcs represent (and are labeled with) topics. Here you can see what topics are available (for publishing or subscribing) for your own programs.
* rostopic list – get a list of active topics
* rostopic echo topic-name – see the data that is being published on this topic (e.g., rostopic echo turtle1/pose)
* rostopic info topic-name – get a bunch of info about a topic. Note: first line tells the message type for the topic
* rosmsg show message-type-name – show details about the message type (i.e., show the names and data types of the components of the message).
* rostopic pub –r rate-in-hz topic-name message-type message-content – publish a message from the command line
* message type names always are of the form package-name/type-name (e.g., turtlesim/Pose)