

Workspacej		Packages		Turtlebot2	
make workspace	<code>mkdir -p ~/ros/indigo/catkin_ws</code>	list	<code>rospack list</code>	Turtlebot	<code>roslaunch turtlebot_bringup minimal.launch</code>
	<code>cd ~/ros/indigo/catkin_ws/</code>	list dependencies	<code>rospack depends &lt;pkg&gt;</code>	make it move	<code>rostopic pub -r 10 /mobile_base/commands/velocity geometry_msgs/Twist '{linear: {x: 0.0, y: 0.0, z: 0.0}, angular: {x: 0.0, y: 0.0, z: -0.7}}'</code>
	<code>catkin_make</code>	cd pkg dir	<code>roscd &lt;pkg&gt;</code>	env	<code>TURTLEBOT_3D_SENSOR=kinect</code>
add to source	<code>echo "\$PWD/level/setup.bash" &gt;&gt; ~/.bashrc</code>	rosmmsg	<code>[ list   show ]</code>	tutorials	<a href="http://wiki.ros.org/Robots/TurtleBot?distro=indigo">http://wiki.ros.org/Robots/TurtleBot?distro=indigo</a>
Environment		Rosbags and topic		visualisation rvis 5.1.3 kinect	Teleoperation 5.2.[1-2-4]
Display	<code>printenv   grep ROS</code>	rosbag	<code>[ info   play -l ]</code>	keyboard joystick rviz_interactive mapping 5.3	
Turtlebot	<code>ROS_MASTER_URI=http://localhost:11311</code>		<code>record [-a   &lt;pkg&gt; &lt;pkg&gt;] -O filename [--clock]</code>		
	<code>ROS_HOSTNAME=&lt;TURTLEBOT_IP&gt;</code>	roscd	<code>[ list   info   ping   kill ]</code>		
Workstation	<code>ROS_MASTER_URI=http://&lt;TURTLEBOT_IP&gt;:11311</code>	rostopic	<code>[ list   info   echo   pub ]</code>		
	<code>ROS_HOSTNAME=&lt;PC_IP&gt;</code>	for gui	<code>rqt_bag &lt;pkg&gt;   rqt_graph</code>		
		roscd	<code>enable_statistics   set &lt;param&gt; true</code>		



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