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| Task. No.: | 2 | Points: | 5 | Hello World! |

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| Objectives:  1. Create ROS workspace. 2. Create ROS package. 3. Create ROS node. |

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| Description: This exercise aims to create a package and run a simple node to publish Hello World! message. |

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| Step | Action |
| 1 | Create *catkin\_ws* folder and *src* folder inside it. |
| 2 | Initialize the workspace with *catkin\_init\_workspace* command. You should be in the *src* folder. |
| 3 | Build the workspace with *catkin\_make* command. You should be in the *catkin\_ws* folder. |
| 4 | Change the .*bashrc* file and add workspace path to end of it. So that you can access the workspace packages in all terminal sessions. |
| 5 | Go to *src* folder and run *catkin\_create\_pkg* to create a package with *rospy* dependency. |
| 6 | Open *Cmakelists.txt,* and *package.xml* files and see their contents. |
| 7 | Compile the workspace with *catkin\_make* command. |
| 8 | Create a simple node with Python to print the following messages. Call it hellow\_world\_node.  $ rosrun my_first_ros_pkg hello_world_node I INFO] [1499662568.416826810]: hello world!0 [INFO] [1499662568.516845339]: hello world!1 [INFO] [1499662568.616839553]: hello world!2 [INFO] [1499662568.716806374]: hello world!3 [INFO] [1499662568.816807707]: hello world!4 |
| 9 | Shout down the node with Ctrl+c. |

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