

Workspacej		Packages		Turtlebot2	
make workspace	mkdir -p ~/ros/indigo/catkin_ws	list	rospack list	Turtlebot	roslaunch turtlebot-_bringup minimal.l-aunch
	cd ~/ros/indigo/catkin_ws/	list depend-encies	rospack depends <pkg>	make it move	rostopic pub -r 10 /mobile_base/co-mmands/velocity geometry_msg-s/Twist '{linear: {x: 0.0, y: 0.0, z: 0.0}, angular: {x: 0.0, y: 0.0, z: -0.7}}'
	catkin_make	cd pkg dir	roscd <pkg>		
add to source	echo "\$PWD/d-evel/setup.bash" >> ~/.bashrc	rosmmsg	[list show]	env	TURTLEBOT_3D-_SENSOR=kinect
Environment		Rosbags and topic		tutorials	http://wiki.ros.org/R-obots/TurtleBot?di-stro=indigo
Display	printenv grep ROS	rosbag	[info play -l]	visualisation	rvis 5.1.3 kinect
Turtlebot	ROS_MASTER_U-RI=http://localhos-t:11311		record [-a <pkg> <pkg>] -O filename [--clock]	Teleoperation	5.2.[1-2-4]
	ROS_HOSTNAME=<TURTLEBOT_IP>	roscd	[list info ping kill]	keyboard joystick	rviz_interactive mapping 5.3
Workst-ation	ROS_MASTER_U-RI=http://<TURT-LEBOT_IP>:11311	rostopic	[list info echo pub]		
	ROS_HOSTNAME=<PC_IP>	for gui	rqt_bag <pkg> rqt_graph		
		rosparm	enable_statistics use_sim_time		
		set <pa-ram> true			