

09/22/18

Launch Turtlesim turtlesim_tlh.launch Use Keyboard

File is turtlesim_tlh.launch in catkin_ws

```
harman@D104-45931:~/catkin_ws$ ls -la |grep turtlesim
```

```
-rwxrwxr-x 1 harman harman 1861 Sep 17 2017 turtlesim1.py
-rw-rw-r-- 1 harman harman 308 Sep 22 16:56 turtlesim.launch
drwxrwxr-x 2 harman harman 4096 Sep 17 11:07 turtlesim_py
-rw-rw-r-- 1 harman harman 314 Sep 22 18:52 turtlesim_tlh.launch
```

SIMPLE LAUNCH FILE (MODIFIED FROM TURTLE_TF PACKAGE)

(See TF Practice on website for details of turtle_tf package)

```
<launch>
  <!-- Turtlesim Node-->
  <node pkg="turtlesim" type="turtlesim_node" name="sim"/>
  <node pkg="turtlesim" type="turtle_teleop_key" name="teleop" output="screen"/>
  <!-- Axes -->
  <param name="scale_linear" value="2" type="double"/>
  <param name="scale_angular" value="2" type="double"/>
</launch>
```

LAUNCH DIRECTLY – NOT IN PACKAGE

```
harman@D104-45931:~/catkin_ws$ roslaunch turtlesim_tlh.launch
```

```
... logging to /home/harman/.ros/log/adc365ae-bec2-11e8-ad7f-9cb6d00f6f89/roslaunch-D104-45931-16891.log
```

Checking log directory for disk usage. This may take awhile.

Press Ctrl-C to interrupt

Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://D104-45931:41023/

SUMMARY

=====

PARAMETERS

- * /rostdistro: kinetic
- * /rosversion: 1.12.7
- * /scale_angular: 2.0
- * /scale_linear: 2.0

NODES

```
/
  sim (turtlesim/turtlesim_node)
  teleop (turtlesim/turtle_teleop_key)
```

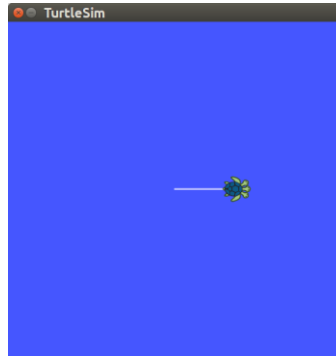
auto-starting new master

process[master]: started with pid [16902]

ROS_MASTER_URI=http://localhost:11311

setting /run_id to adc365ae-bec2-11e8-ad7f-9cb6d00f6f89
process[rosout-1]: started with pid [16915]
started core service [/rosout]
process[sim-2]: started with pid [16922]
process[teleop-3]: started with pid [16933]
Reading from keyboard

Use arrow keys to move the turtle.



```
harman@D104-45931:~$ rosnodetree
rosout
sim
teleop
```

(Renamed in launch file)

```
harman@D104-45931:~$ rosparam list
/background_b
/background_g
/background_r
/rosdistro
/roslaunch/uris/host_d104_45931__41023
/rosversion
/run_id
/scale_angular
/scale_linear
```