ROS Classic Knowledge Map (Python)

Click on the links to go to the wiki page where to learn more about that subject

ROS BASICS (Python) central node connecting to:

- **TOPICS** — Publisher, Subscriber
- **SERVICES** — Server, Client
- **ACTIONS** — Server, AxClient, Client
- **MESSAGES** — topic msg (msg), service msg (srv), action msg (action)
- **DEBUGGING TOOLS** — rosbag, rviz, rosconsole, rqt, roswtf
- **TF** — tf listener, Static Transform, view frames, tf broadcaster
- **URDF** — visual model, xacro, joints, physical prop., robot_state_publisher
- **CATKIN** — package.xml, CMakeLists.txt, ws tools, catkin_make
- **ROS PACKAGES** — launch file, catkin_create_pkg
- **ROS NODES** — Initialization, Shutdown
- **CALLBACK QUEUE**
- **ROS CLI** — rosrun, roslaunch, rosservice, rosparam, roscd, rossrv, rosmsg, roscore, rosnode, rostopic
- **ENVIROMENTAL VARIABLES** — ROS_PACKAGE_PATH, PYTHONPATH, ROS_MASTER_URI, ROS_IP
- **ROSCORE**
- **ROS INSTALL** — rosdep
- **ROS PARAM SERVER** — Dynamic Reconfigure, Client Library
- **ROS LOGGING**

The Construct — For ROS Developers

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