rospy.init\_node('guide')

motor\_pub = rospy.Publisher('xycar\_motor\_msg', Int32MultiArray, queue\_size=1)

ultra\_sub = rospy.Subscriber('ultrasonic', Int32MultiArray, callback)

xycar\_msg = Int32MultiArray()

angle = 0

speed = 25

beforeFr = 0

while not rospy.is\_shutdown():

xycar\_msg.data = [angle, speed]

motor\_pub.publish(xycar\_msg)

lrRange = abs(274 - (l + r))

flrRange = abs(224 - (fl + fr))

if beforeFr == 0 or abs(fr - beforeFr) < 30:

beforeFr = fr

if lrRange <= 1 or flrRange <= 1:

angle = 0

if beforeFr + 50 <= fr:

angle = 100

elif fr < 5 or r < 5:

angle = -50

elif fl < 5 or l < 5:

angle = 50

elif fl < fr:

angle = 100

elif fl > fr:

angle = -100