~/ros2_ws3/src/talkerlistener/talkerlistener/listener.py

```python
1   import rclpy
2   from rclpy.node import Node
3   from std_msgs.msg import String
4
5   class ListenerNode(Node):
6       def __init__(self):
7           super().__init__('listener')
8           self.subscription = self.create_subscription(
9               String,
10              'chatter',
11              self.listener_callback,
12              10)
13          self.subscription
14
15      def listener_callback(self, msg):
16          self.get_logger().info(f'Received: "{msg.data}"')
17
18  def main(args=None):
19      rclpy.init(args=args)
20      node = ListenerNode()
21      rclpy.spin(node)
22      node.destroy_node()
23      rclpy.shutdown()
```