Assignment 4

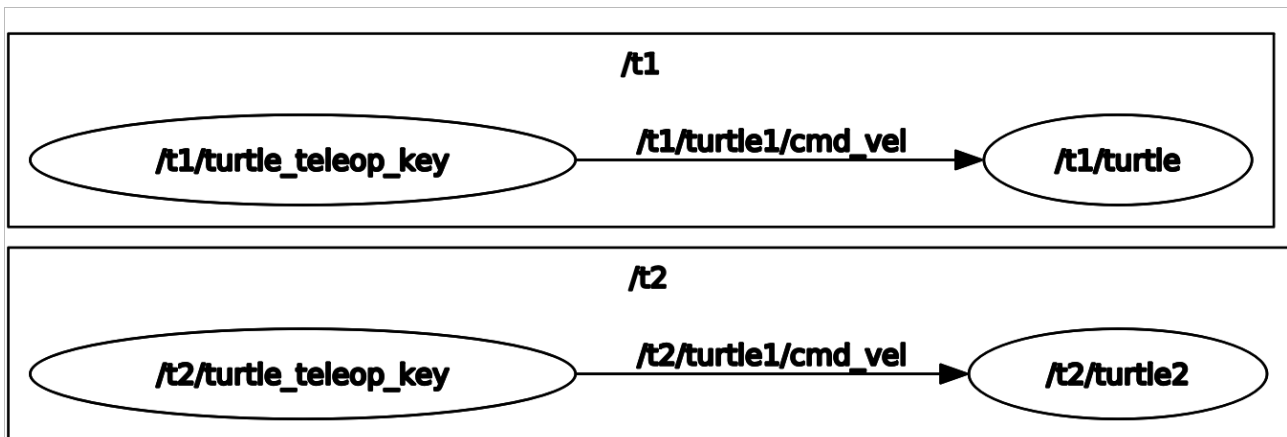Launch file for controlling two different turtles in two different screen with two different keyboard

```
1 <launch>
2     <group ns ="t1">
3         <node name="turtle" pkg="turtlesim" type="turtlesim_node"></node>
4         <node name="turtle_teleop_key" pkg="turtlesim" type="turtle_teleop_key" launch-prefix="xterm -e"></node>
5         <param name="turtle/background_r" value="255"></param>
6         <param name="turtle/background_b" value="0"></param>
7         <param name="turtle/background_g" value="0"></param>
8     </group>
9
10    <group ns ="t2">
11        <node name="turtle2" pkg="turtlesim" type="turtlesim_node"></node>
12        <node name="turtle_teleop_key" pkg="turtlesim" type="turtle_teleop_key" launch-prefix="xterm -e"></node>
13
14    </group>
15 </launch>
16
17
18
19
```

For changing
Background
color to
Red

RQT GRAPH

/t1

/t1/turtle_teleop_key   /t1/turtle1/cmd_vel → /t1/turtle

/t2

/t2/turtle_teleop_key   /t2/turtle1/cmd_vel → /t2/turtle2

```xml
<launch>
        <node name="turtle" pkg="turtlesim" type="turtlesim_node"/>
        <node pkg="robot_move" name="spawn" type="spawn_client.py"/>
        <node name="turtle_teleop_key2" pkg="turtlesim" type="turtle_teleop_key" launch-prefix="xterm -e">
        </node>
        <node name="turtle_teleop_key1" pkg="turtlesim" type="turtle_teleop_key" launch-prefix="xterm -e">
                <remap from="/turtle1/cmd_vel" to="/turtle3/cmd_vel"/>
        </node>

</launch>
```

Spawn_client.py

```python
#!/usr/bin/env python

import rospy
from turtlesim.srv import *

rospy.wait_for_service('/spawn')
spawner = rospy.ServiceProxy('/spawn', Spawn)
spawner(4, 2, 0, 'turtle3')
```

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