Task2:

```
yahboom@VM:~/roscourse_ws$ colcon build --symlink-install
[0.368s] WARNING:colcon.colcon_core.package_identification:Failed to parse ROS package manifest in 'src/webcam': Error(s) in
package 'src/webcam/package.xml':
Invalid email ""mr_vincent_hu@163.com"" for person "yahboom"
Starting >>> webcam
Finished <<< webcam [1.51s]

Summary: 1 package finished [2.14s]
```
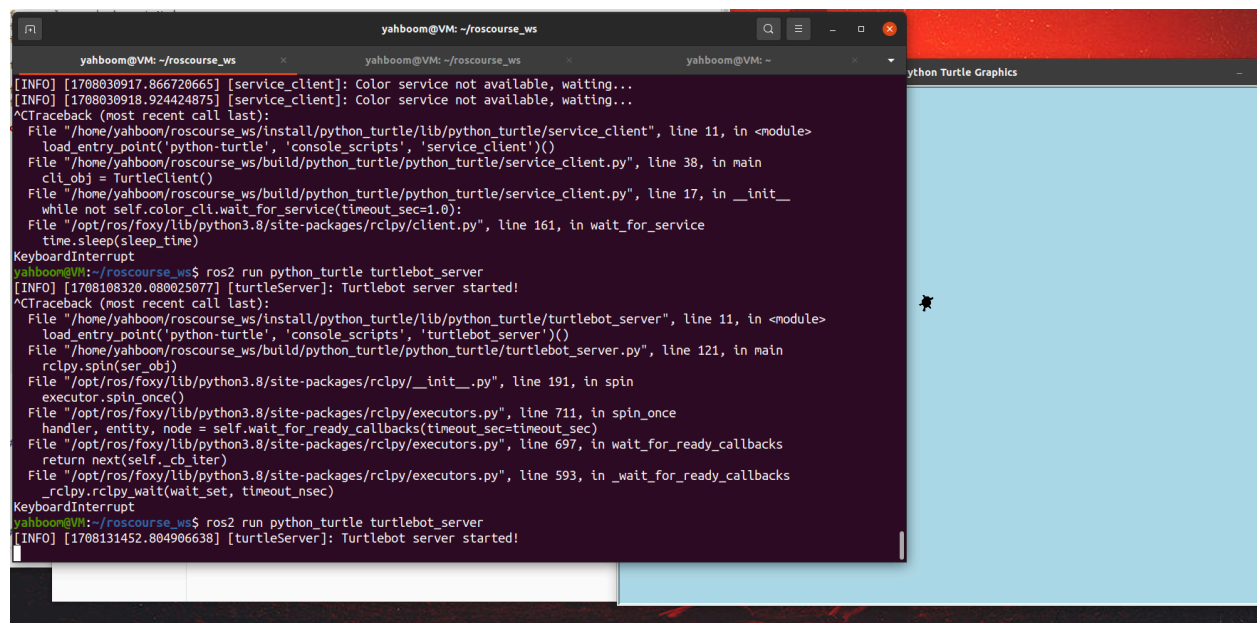
Task3:

```
yahboom@VM:~/roscourse_ws$ source ./install/setup.bash
yahboom@VM:~/roscourse_ws$ ros2 interface show turtle_interfaces/msg/TurtleMsg
string name
geometry_msgs/Pose turtle_pose
string color
yahboom@VM:~/roscourse_ws$ ros2 interface show turtle_interfaces/srv/SetPose
geometry_msgs/PoseStamped turtle_pose
---
int8 ret
yahboom@VM:~/roscourse_ws$ ros2 interface show turtle_interfaces/srv/SetColor
string color
---
int8 ret
```
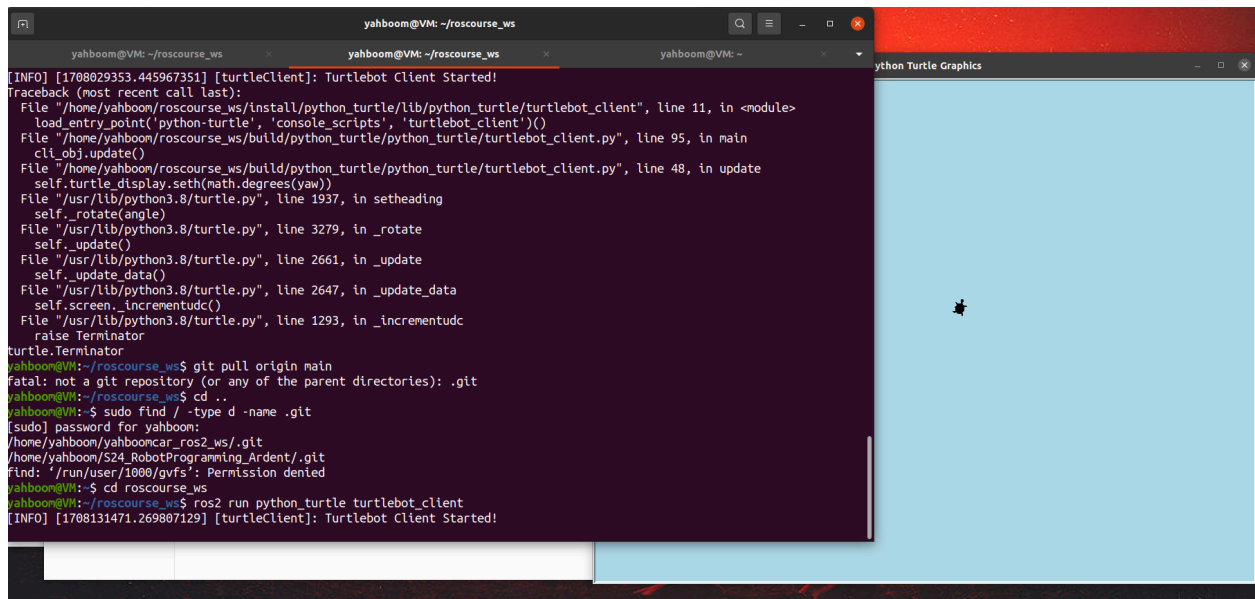
Task4:

Step 7:

server:

Client:


```
[INFO] [1708029353.445967351] [turtleClient]: Turtlebot Client Started!
Traceback (most recent call last):
  File "/home/yahboom/roscourse_ws/install/python_turtle/lib/python_turtle/turtlebot_client", line 11, in <module>
    load_entry_point('python-turtle', 'console_scripts', 'turtlebot_client')()
  File "/home/yahboom/roscourse_ws/build/python_turtle/python_turtle/turtlebot_client.py", line 95, in main
    cli_obj.update()
  File "/home/yahboom/roscourse_ws/build/python_turtle/python_turtle/turtlebot_client.py", line 48, in update
    self.turtle_display.seth(math.degrees(yaw))
  File "/usr/lib/python3.8/turtle.py", line 1937, in setheading
    self._rotate(angle)
  File "/usr/lib/python3.8/turtle.py", line 3279, in _rotate
    self._update()
  File "/usr/lib/python3.8/turtle.py", line 2661, in _update
    self._update_data()
  File "/usr/lib/python3.8/turtle.py", line 2647, in _update_data
    self.screen._incrementudc()
  File "/usr/lib/python3.8/turtle.py", line 1293, in _incrementudc
    raise Terminator
turtle.Terminator
yahboom@VM:~/roscourse_ws$ git pull origin main
fatal: not a git repository (or any of the parent directories): .git
yahboom@VM:~/roscourse_ws$ cd ..
yahboom@VM:~$ sudo find / -type d -name .git
[sudo] password for yahboom:
/home/yahboom/yahboomcar_ros2_ws/.git
/home/yahboom/S24_RobotProgramming_Ardent/.git
find: '/run/user/1000/gvfs': Permission denied
yahboom@VM:~$ cd roscourse_ws
yahboom@VM:~/roscourse_ws$ ros2 run python_turtle turtlebot_client
[INFO] [1708131471.269807129] [turtleClient]: Turtlebot Client Started!
```

Step16:
ros2 run python_turtle turtlebot_server


```
yahboom@VM:~/roscourse_ws$ ros2 run python_turtle turtlebot_server
[INFO] [1708131637.295410625] [turtleServer]: Turtlebot server started!
```
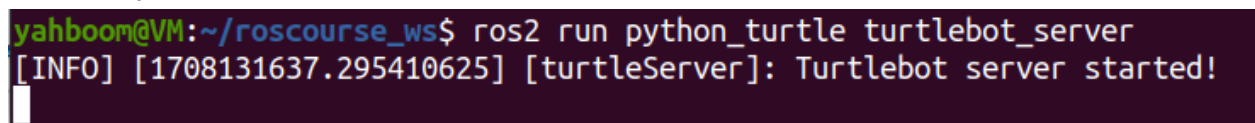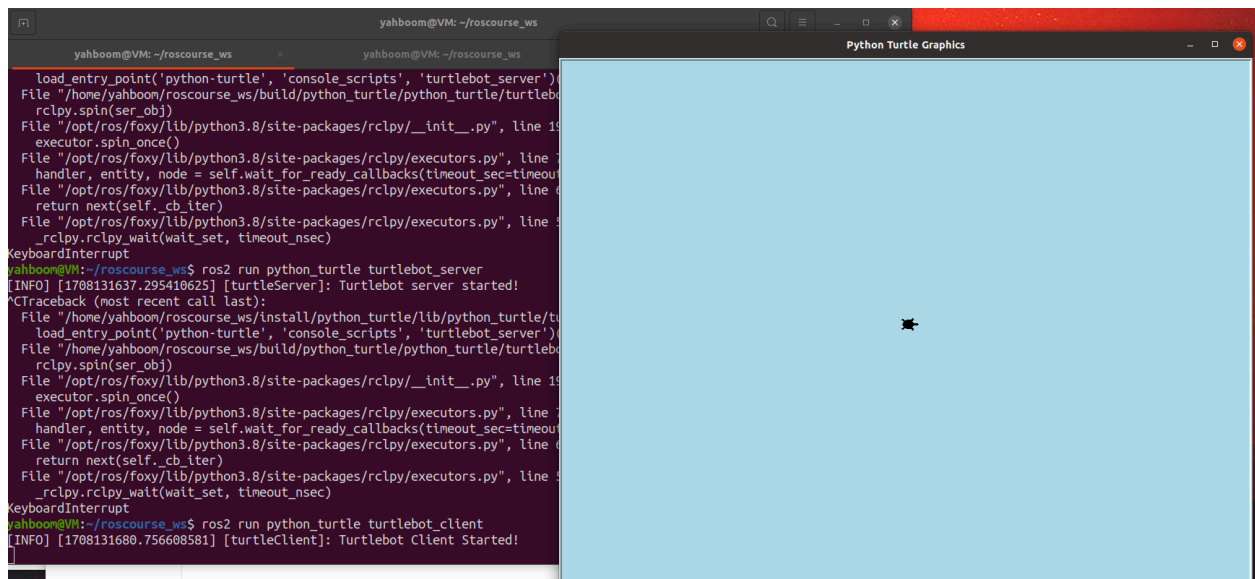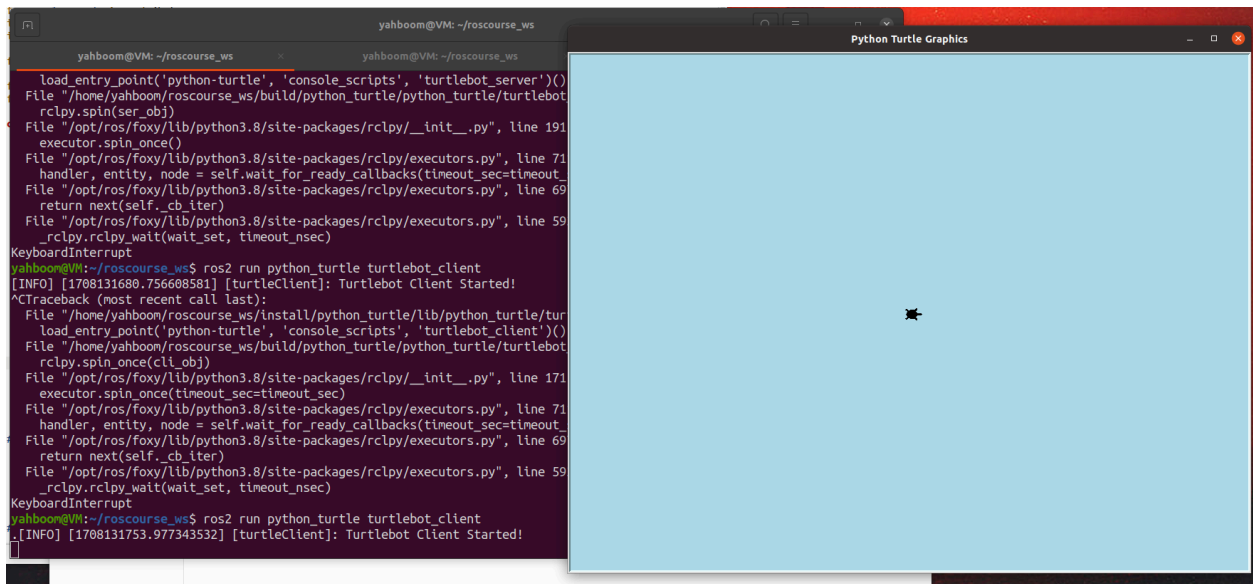
ros2 run python_turtle turtlebot_client


```
    load_entry_point('python-turtle', 'console_scripts', 'turtlebot_server')(
  File "/home/yahboom/roscourse_ws/build/python_turtle/python_turtle/turtlebo
    rclpy.spin(ser_obj)
  File "/opt/ros/foxy/lib/python3.8/site-packages/rclpy/__init__.py", line 19
    executor.spin_once()
  File "/opt/ros/foxy/lib/python3.8/site-packages/rclpy/executors.py", line 7
    handler, entity, node = self.wait_for_ready_callbacks(timeout_sec=timeout
  File "/opt/ros/foxy/lib/python3.8/site-packages/rclpy/executors.py", line 6
    return next(self._cb_iter)
  File "/opt/ros/foxy/lib/python3.8/site-packages/rclpy/executors.py", line 5
    _rclpy.rclpy_wait(wait_set, timeout_nsec)
KeyboardInterrupt
yahboom@VM:~/roscourse_ws$ ros2 run python_turtle turtlebot_server
[INFO] [1708131637.295410625] [turtleServer]: Turtlebot server started!
^CTraceback (most recent call last):
  File "/home/yahboom/roscourse_ws/install/python_turtle/lib/python_turtle/tu
    load_entry_point('python-turtle', 'console_scripts', 'turtlebot_server')(
  File "/home/yahboom/roscourse_ws/build/python_turtle/python_turtle/turtlebo
    rclpy.spin(ser_obj)
  File "/opt/ros/foxy/lib/python3.8/site-packages/rclpy/__init__.py", line 19
    executor.spin_once()
  File "/opt/ros/foxy/lib/python3.8/site-packages/rclpy/executors.py", line 7
    handler, entity, node = self.wait_for_ready_callbacks(timeout_sec=timeout
  File "/opt/ros/foxy/lib/python3.8/site-packages/rclpy/executors.py", line 6
    return next(self._cb_iter)
  File "/opt/ros/foxy/lib/python3.8/site-packages/rclpy/executors.py", line 5
    _rclpy.rclpy_wait(wait_set, timeout_nsec)
KeyboardInterrupt
yahboom@VM:~/roscourse_ws$ ros2 run python_turtle turtlebot_client
[INFO] [1708131680.756608581] [turtleClient]: Turtlebot Client Started!
]
```

ros2 run pyython_turtle service_client