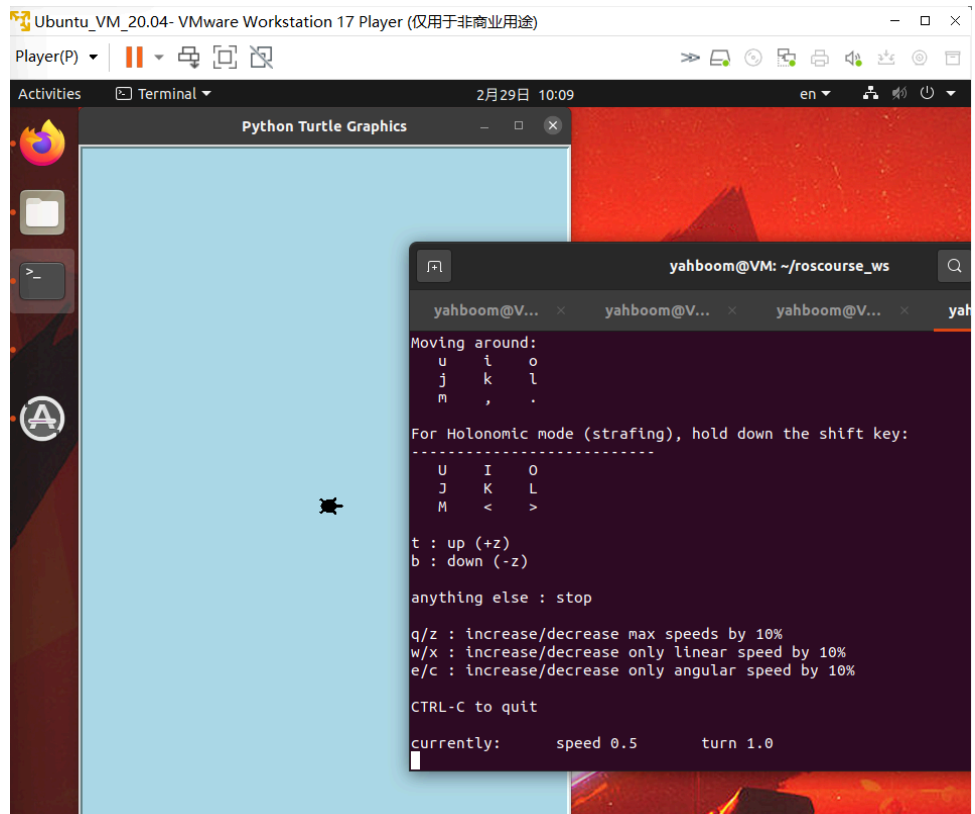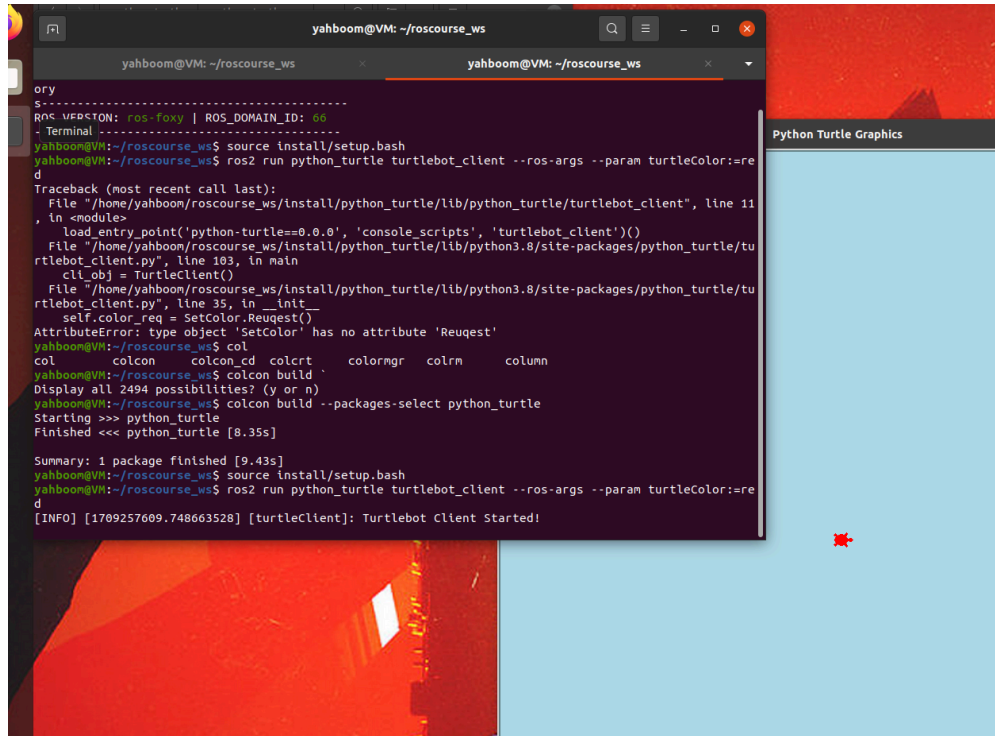TASK1 STEP 17:

TASK2 EDITED CODE:

```
15
16 class TurtleClient(Node):
17     def __init__(self):
18         super().__init__('turtleClient')
19         self.declare_parameter(
20     'penSize',
21     1,  # Default pen size
22     ParameterDescriptor(description='Initial pen size for the turtle. Determines the
   thickness of the line the turtle draws.')
23 )
24         penSize = self.get_parameter('penSize').get_parameter_value().integer_value
25         self.turtle_display.pensize(penSize)
26         ####set pen size here####
27         self.declare_parameter('turtleColor', 'black',
28         ParameterDescriptor(description= 'turtle color'))
29         #### Display/Turtle Setup ####
30         self.screen = turtle.Screen()
```
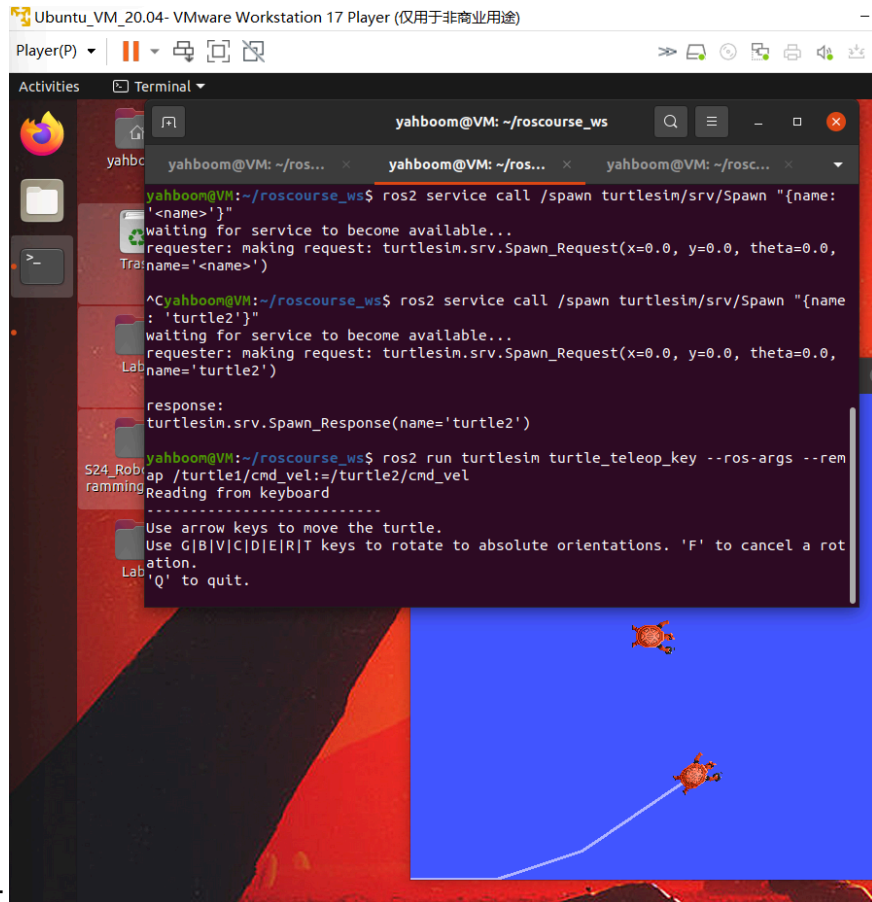
TASK2 STEP 12:


```
ory
s-------------------------------------------
ROS_VERSION: ros-foxy | ROS_DOMAIN_ID: 66
- Terminal -----------------------------------
yahboom@VM:~/roscourse_ws$ source install/setup.bash
yahboom@VM:~/roscourse_ws$ ros2 run python_turtle turtlebot_client --ros-args --param turtleColor:=re
d
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==0.0.0', 'console_scripts', 'turtlebot_client')()
  File "/home/yahboom/roscourse_ws/install/python_turtle/lib/python3.8/site-packages/python_turtle/tu
rtlebot_client.py", line 103, in main
    cli_obj = TurtleClient()
  File "/home/yahboom/roscourse_ws/install/python_turtle/lib/python3.8/site-packages/python_turtle/tu
rtlebot_client.py", line 35, in __init__
    self.color_req = SetColor.Reuqest()
AttributeError: type object 'SetColor' has no attribute 'Reuqest'
yahboom@VM:~/roscourse_ws$ col
col          colcon       colcon_cd  colcrt      colormgr   colrm        column
yahboom@VM:~/roscourse_ws$ colcon build `
Display all 2494 possibilities? (y or n)
yahboom@VM:~/roscourse_ws$ colcon build --packages-select python_turtle
Starting >>> python_turtle
Finished <<< python_turtle [8.35s]

Summary: 1 package finished [9.43s]
yahboom@VM:~/roscourse_ws$ source install/setup.bash
yahboom@VM:~/roscourse_ws$ ros2 run python_turtle turtlebot_client --ros-args --param turtleColor:=re
d
[INFO] [1709257609.748663528] [turtleClient]: Turtlebot Client Started!
```

task 4 step3:

Player(P) ▾

Activities   Terminal ▾

yahboom@VM: ~/roscourse_ws

yahboom@VM: ~/ros...   yahboom@VM: ~/ros...   yahboom@VM: ~/rosc...

```
yahboom@VM:~/roscourse_ws$ ros2 service call /spawn turtlesim/srv/Spawn "{name:
'<name>'}"
waiting for service to become available...
requester: making request: turtlesim.srv.Spawn_Request(x=0.0, y=0.0, theta=0.0,
name='<name>')

^Cyahboom@VM:~/roscourse_ws$ ros2 service call /spawn turtlesim/srv/Spawn "{name
: 'turtle2'}"
waiting for service to become available...
requester: making request: turtlesim.srv.Spawn_Request(x=0.0, y=0.0, theta=0.0,
name='turtle2')

response:
turtlesim.srv.Spawn_Response(name='turtle2')

yahboom@VM:~/roscourse_ws$ ros2 run turtlesim turtle_teleop_key --ros-args --rem
ap /turtle1/cmd_vel:=/turtle2/cmd_vel
Reading from keyboard
---------------------------
Use arrow keys to move the turtle.
Use G|B|V|C|D|E|R|T keys to rotate to absolute orientations. 'F' to cancel a rot
ation.
'Q' to quit.
```