**Note:** This tutorial assumes that you have completed the previous tutorials: writing a simple service and client (python) (/ROS/Tutorials/WritingServiceClient%28python%29) (c++) (/ROS/Tutorials/WritingServiceClient%28c%2B%2B%29).

Please ask about problems and questions regarding this tutorial on answers.ros.org (http://answers.ros.org). Don't forget to include in your question the link to this page, the versions of your OS & ROS, and also add appropriate tags.

# Examining the Simple Service and Client

**Description:** This tutorial examines running the simple service and client.

**Tutorial Level:** BEGINNER

**Next Tutorial:** Recording and playing back data (/ROS/Tutorials/Recording%20and%20playing%20back%20data)

**Sommaire**



# 1. Running the Service

Let's start by running the service:

```
$ rosrun beginner_tutorials add_two_ints_server     (C++)
$ rosrun beginner_tutorials add_two_ints_server.py  (Python)
```

You should see something similar to:

```
Ready to add two ints.
```

# 2. Running the Client

Now let's run the client with the necessary arguments:

```
$ rosrun beginner_tutorials add_two_ints_client 1 3     (C++)
$ rosrun beginner_tutorials add_two_ints_client.py 1 3  (Python)
```

You should see something similar to:

```
Requesting 1+3
1 + 3 = 4
```

Now that you've successfully run your first server and client, let's learn how to record and play back data (/ROS/Tutorials/Recording%20and%20playing%20back%20data).

# 3. Further examples on Service and Client nodes

If you want to investigate further and get a hands-on example, you can get one here (https://github.com/fairlight1337/ros_service_examples/). A simple Client and Service combination shows the use of custom message types. The Service node is written in C++ while the Client is available in C++, Python and LISP.



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