**Robotic Operating systems and robot simulations**

Name : Girish S

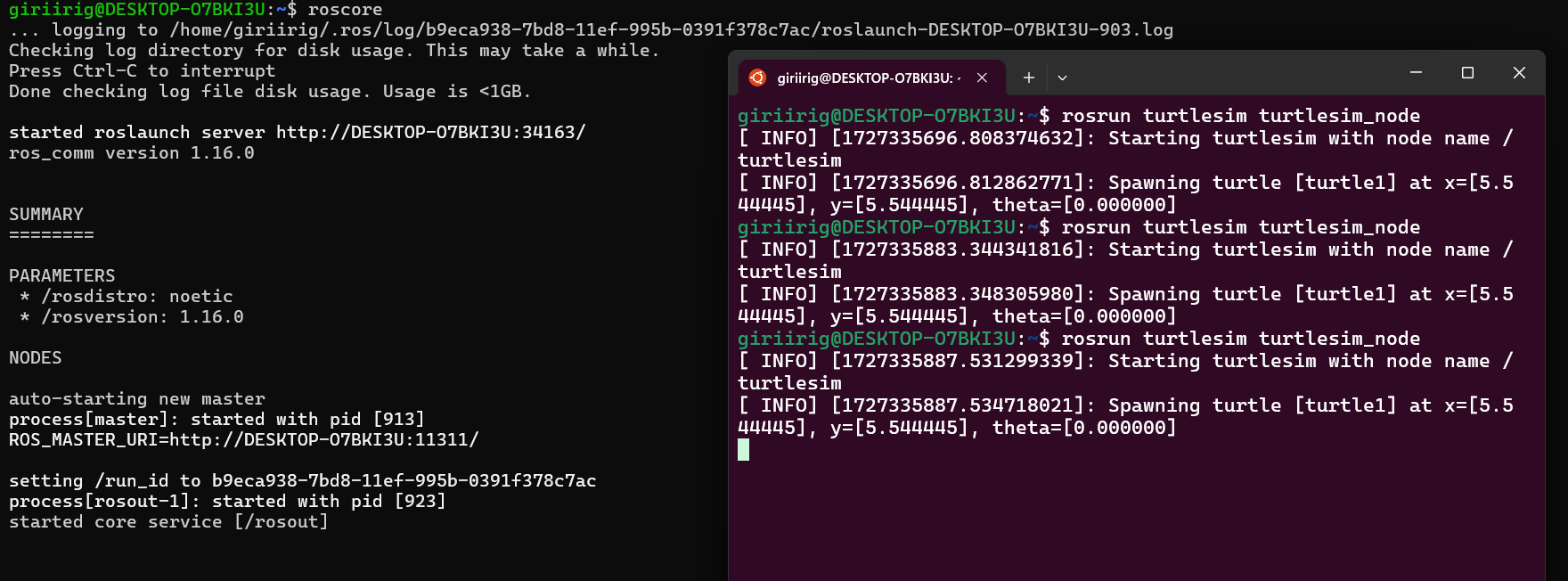
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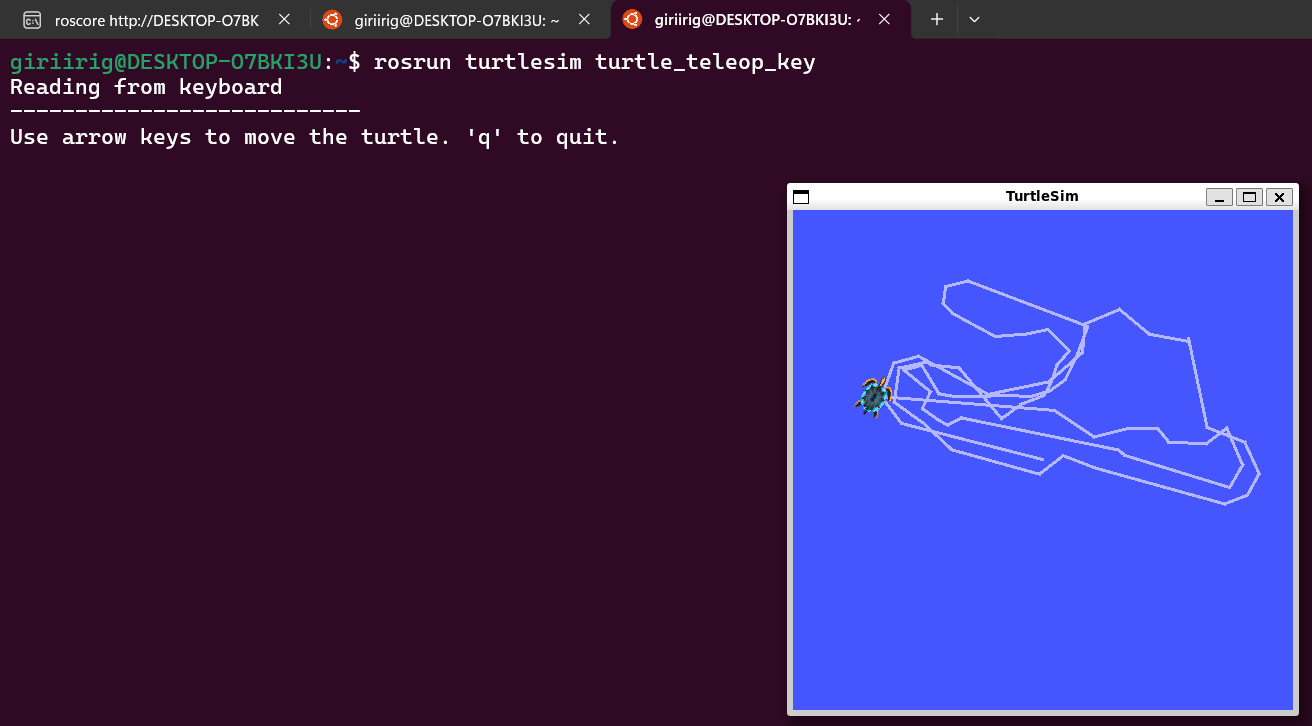
● Download and install the turtlesim package

○ Open a terminal and start the roscore  
*roscore*○ Open another terminal and type  
*sudo apt-get install ros-$(rosversion -d)-turtlesim*○ Run turtlesim

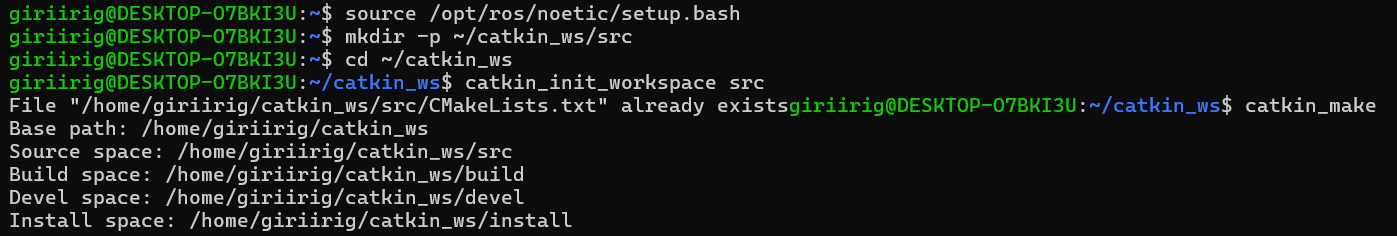
*rosrun turtlesim turtlesim\_node*○ Open another terminal and type  
*rosrun turtlesim turtle\_teleop\_key*

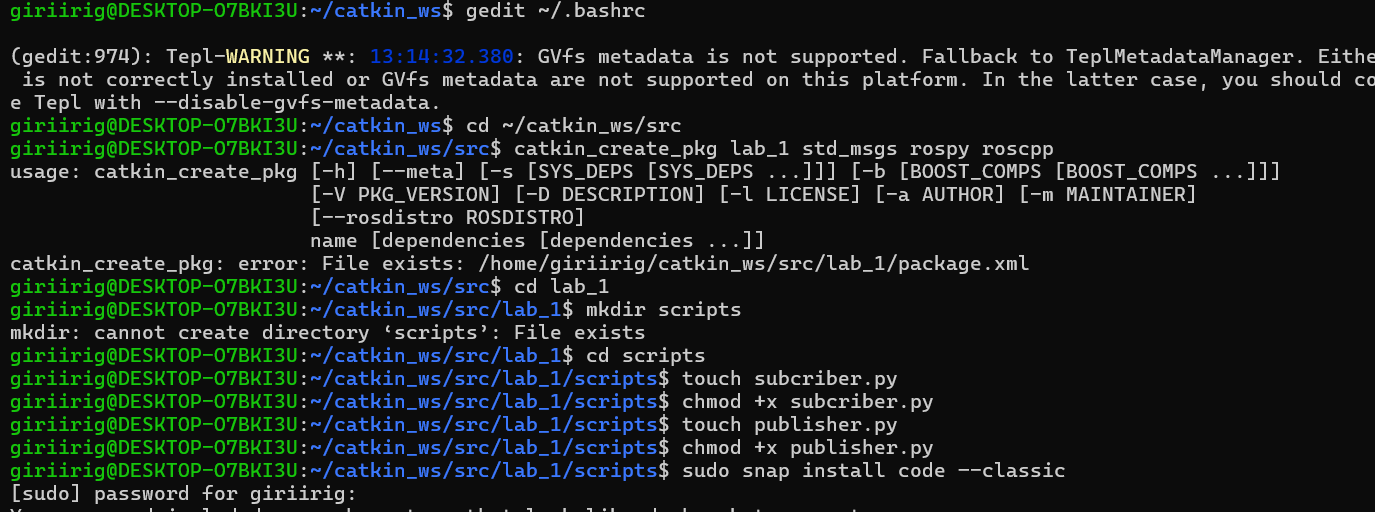
➢ Use the keypad arrow keys to move the turtle around and  
check how the data is getting published in **/cmd\_vel** topic

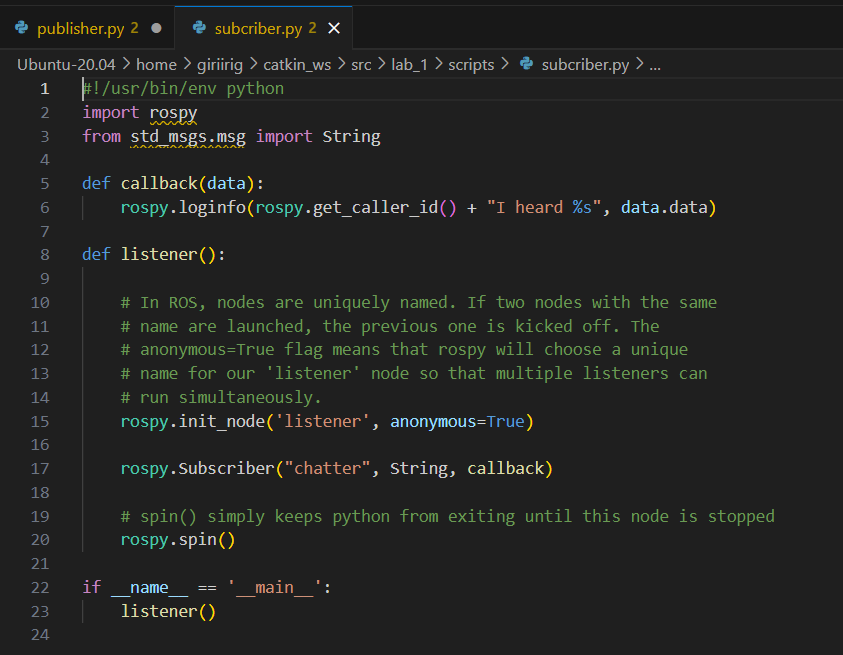




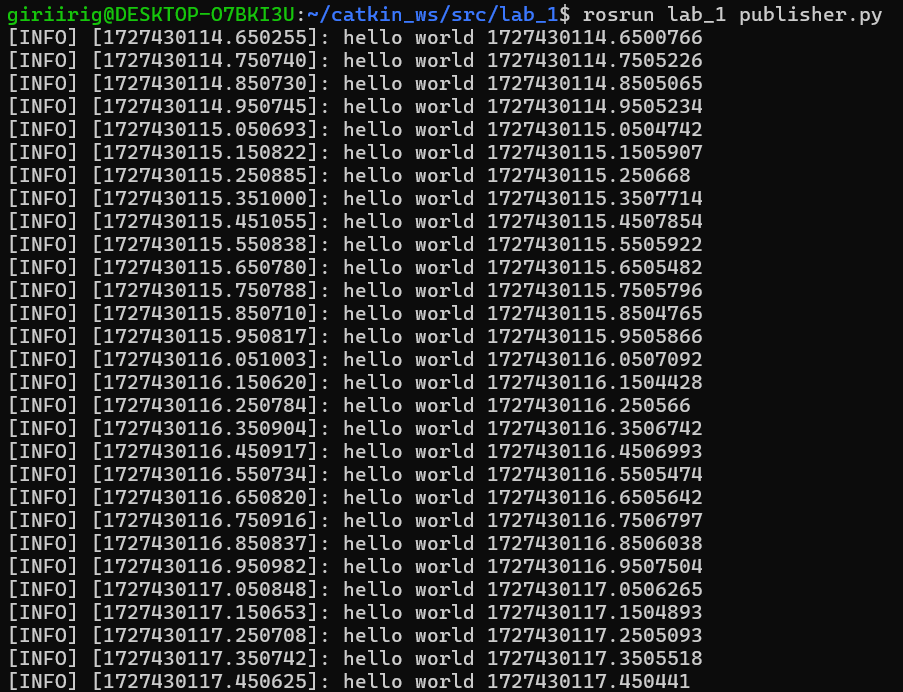
**Catkin workspace setup + publisher and subscriber :**

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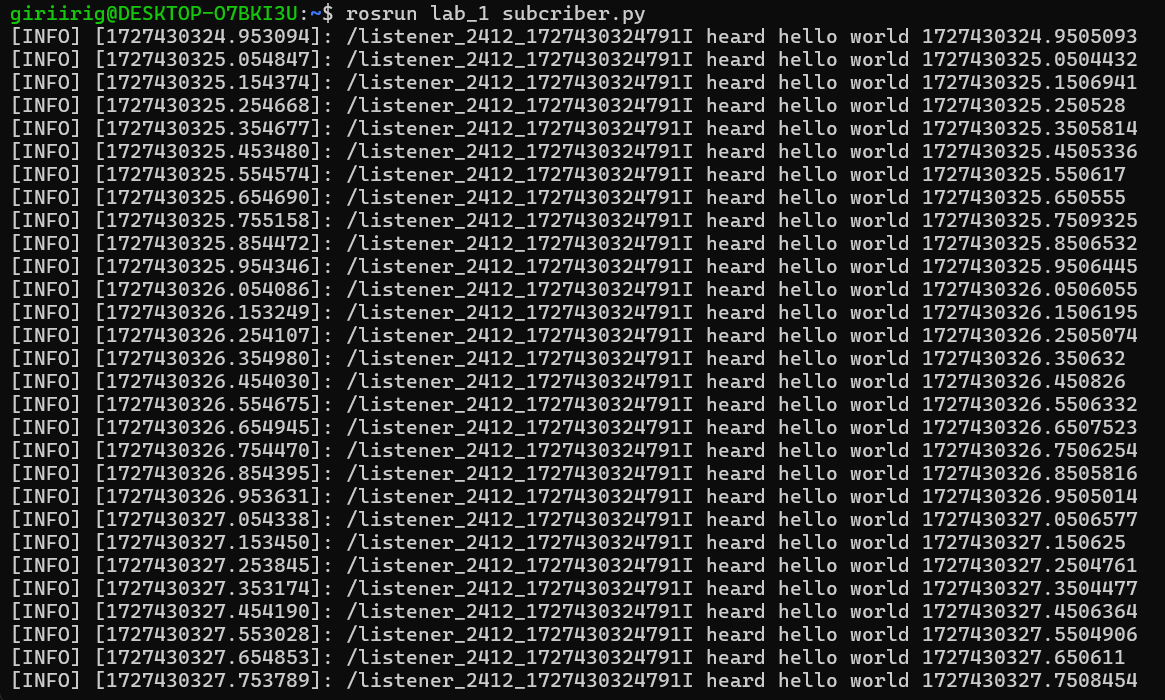
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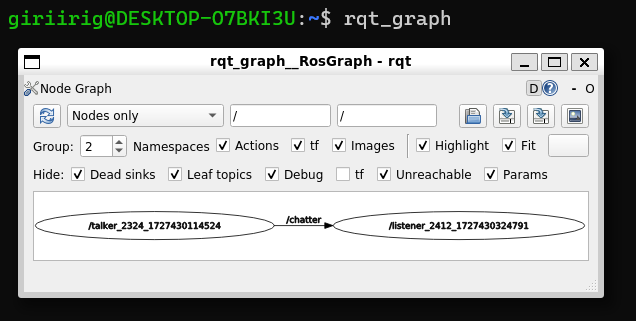


**Output (publisher.py) :**

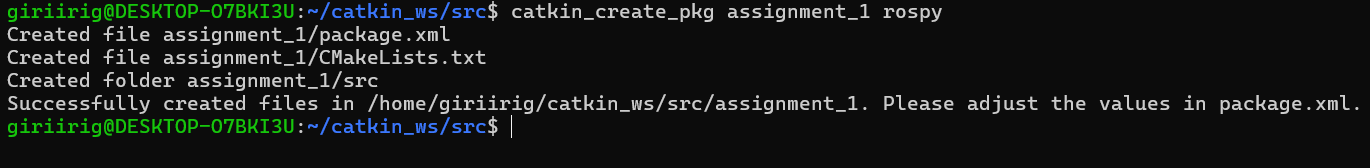


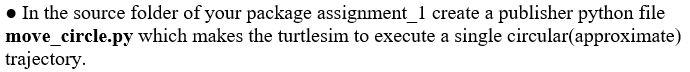
**Output (publisher.py) :**

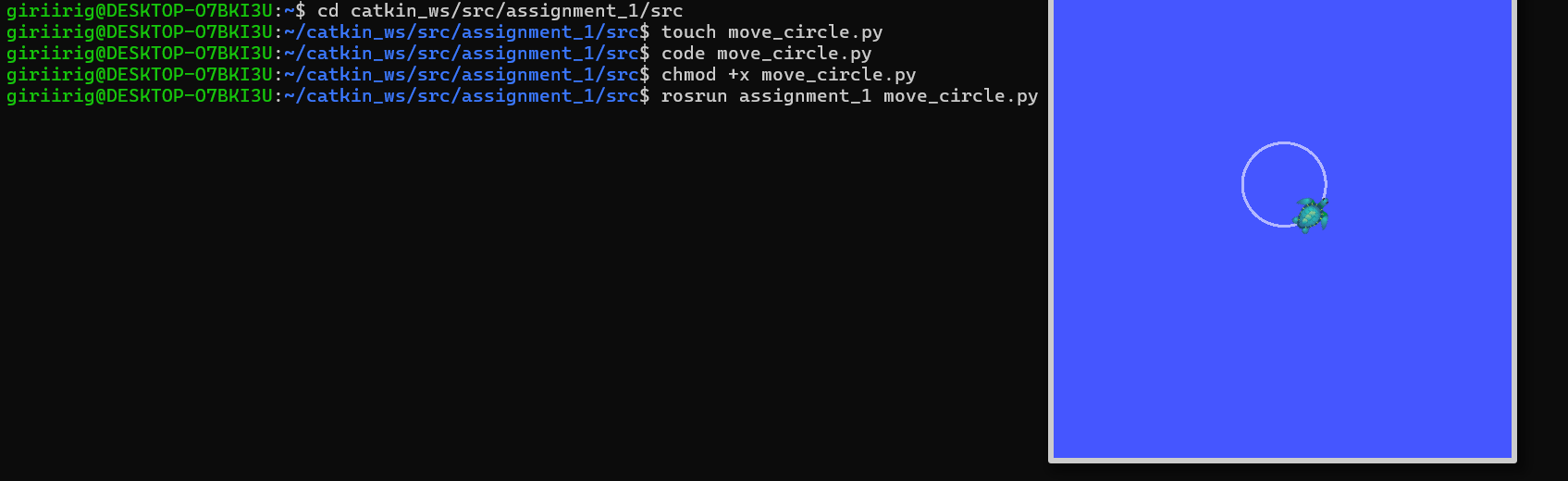




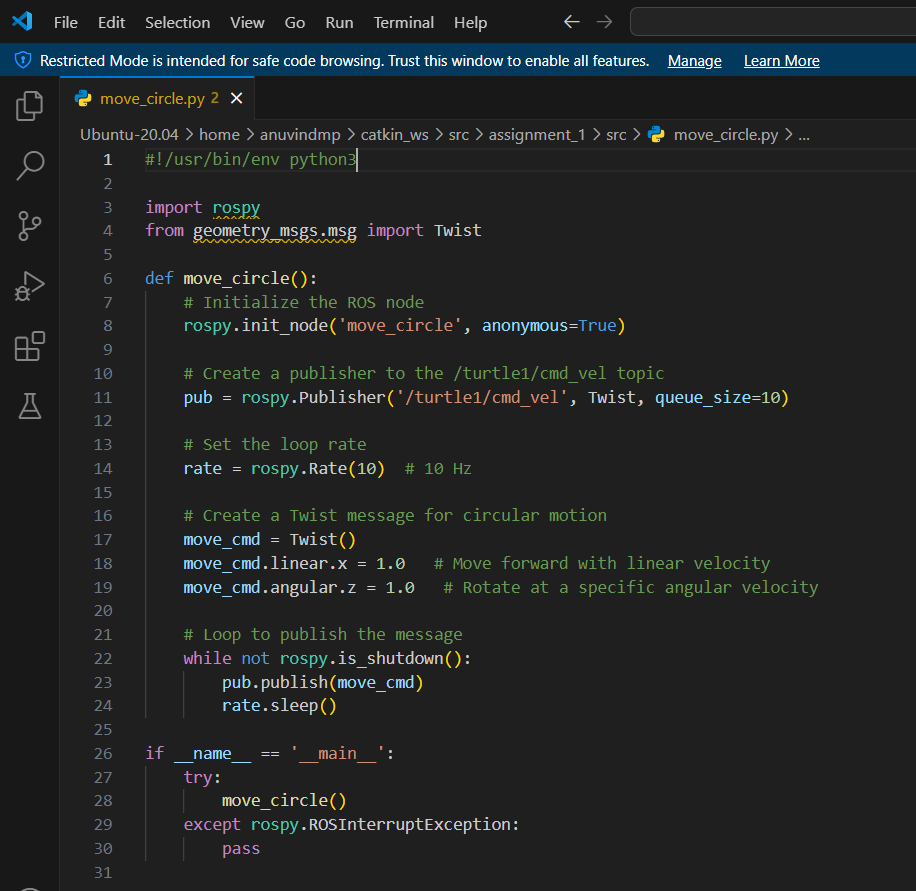


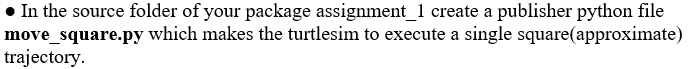


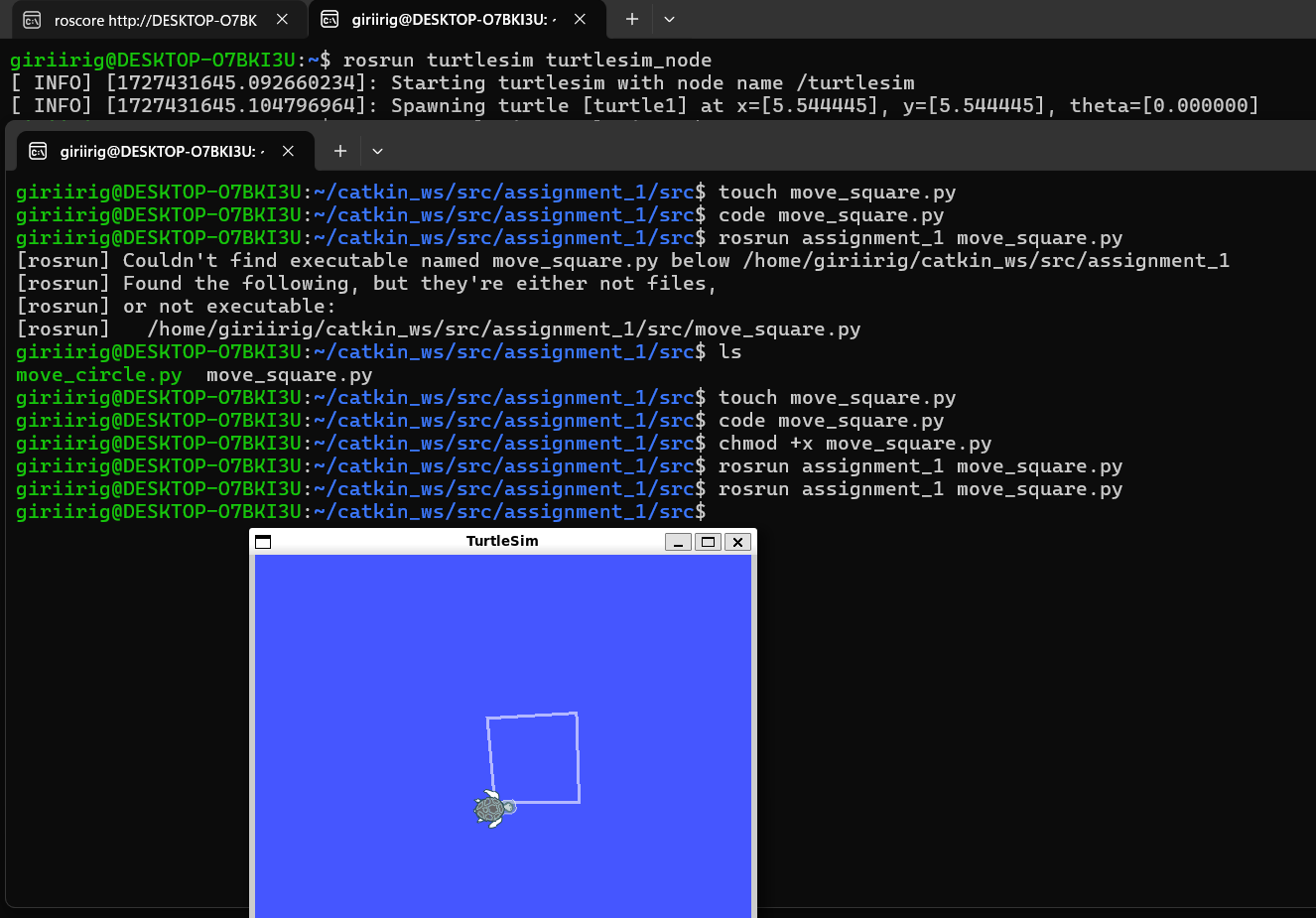




Code :







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