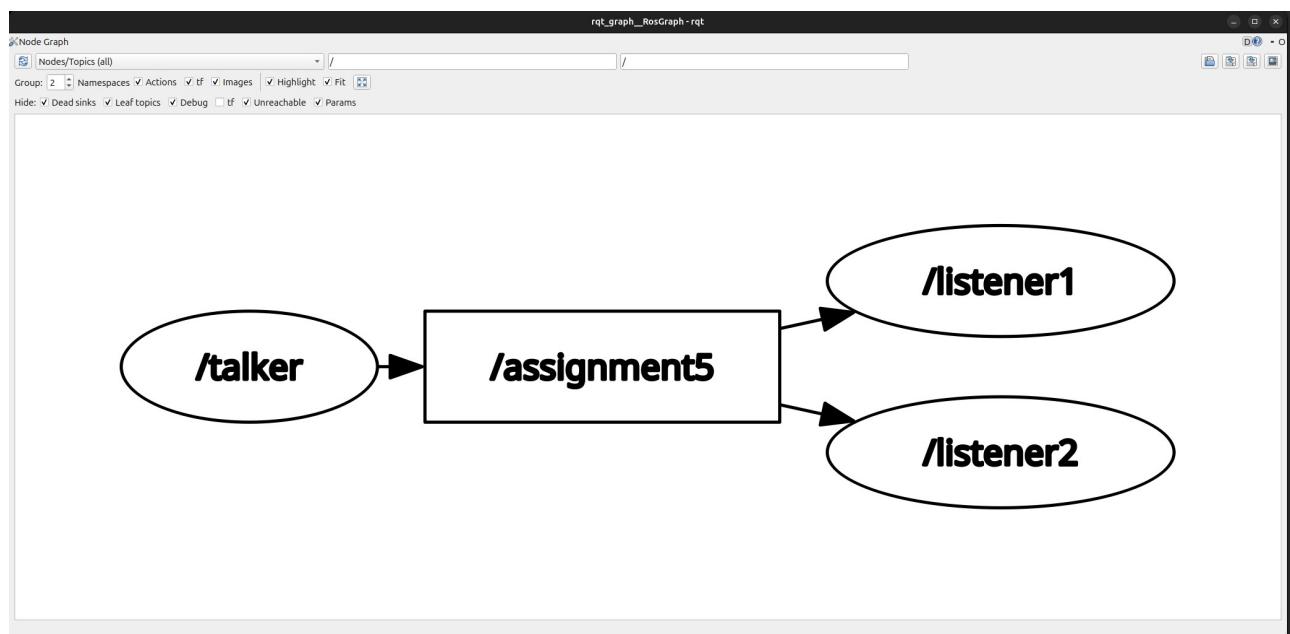


Run in terminal

```
mannaJa@mannaJa:~/study/roS_name_sensei_ws$ ros2 launch assign5_660610840 name_sensei_launch.py
[mINFO] [launch]: All log files can be found below /home/mannaJa/.ros/log/2026-01-06-14-02-19-216602-mannaJa-17708
[mINFO] [launch]: Default logging verbosity is set to INFO
'[INFO] [talker-1]: process started with pid [17711]
[INFO] [listener1-2]: process started with pid [17712]
[INFO] [listener2-3]: process started with pid [17713]
[talker-1] [INFO] [1767682940.110897242] [talker]: myROS say y so EZ: 0
[listener1-2] [INFO] [1767682940.123439591] [listener1]: SUB1 get: "y so EZ: 0"
[listener2-3] [INFO] [1767682940.123683175] [listener2]: SUB2 get: "y so EZ: 0"
[talker-1] [INFO] [1767682940.599949083] [talker]: myROS say y so EZ: 2
[listener1-2] [INFO] [1767682940.601027514] [listener1]: SUB1 get: "y so EZ: 2"
[listener2-3] [INFO] [1767682940.601312213] [listener2]: SUB2 get: "y so EZ: 2"
[talker-1] [INFO] [1767682941.099602895] [talker]: myROS say y so EZ: 4
[listener2-3] [INFO] [1767682941.100484389] [listener2]: SUB2 get: "y so EZ: 4"
[listener1-2] [INFO] [1767682941.100521265] [listener1]: SUB1 get: "y so EZ: 4"
[talker-1] [INFO] [1767682941.600014229] [talker]: myROS say y so EZ: 6
[listener1-2] [INFO] [1767682941.601109650] [listener1]: SUB1 get: "y so EZ: 6"
[listener2-3] [INFO] [1767682941.601156280] [listener2]: SUB2 get: "y so EZ: 6"
[talker-1] [INFO] [1767682942.099836313] [talker]: myROS say y so EZ: 8
[listener1-2] [INFO] [1767682942.101055101] [listener1]: SUB1 get: "y so EZ: 8"
[listener2-3] [INFO] [1767682942.101231866] [listener2]: SUB2 get: "y so EZ: 8"
[talker-1] [INFO] [1767682942.599870756] [talker]: myROS say y so EZ: 10
[listener1-2] [INFO] [1767682942.601004113] [listener1]: SUB1 get: "y so EZ: 10"
[listener2-3] [INFO] [1767682942.601072534] [listener2]: SUB2 get: "y so EZ: 10"
[talker-1] [INFO] [1767682943.099933134] [talker]: myROS say y so EZ: 12
[listener1-2] [INFO] [1767682943.101269494] [listener1]: SUB1 get: "y so EZ: 12"
[listener2-3] [INFO] [1767682943.101334666] [listener2]: SUB2 get: "y so EZ: 12"
[talker-1] [INFO] [1767682943.599838779] [talker]: myROS say y so EZ: 14
[listener2-3] [INFO] [1767682943.600933591] [listener2]: SUB2 get: "y so EZ: 14"
[listener1-2] [INFO] [1767682943.601058222] [listener1]: SUB1 get: "y so EZ: 14"
[talker-1] [INFO] [1767682944.099804773] [talker]: myROS say y so EZ: 16
[listener2-3] [INFO] [1767682944.100980739] [listener2]: SUB2 get: "y so EZ: 16"
[listener1-2] [INFO] [1767682944.101026572] [listener1]: SUB1 get: "y so EZ: 16"
[talker-1] [INFO] [1767682944.599865766] [talker]: myROS say y so EZ: 18
[listener2-3] [INFO] [1767682944.600894111] [listener2]: SUB2 get: "y so EZ: 18"
[listener1-2] [INFO] [1767682944.6009996081] [listener1]: SUB1 get: "y so EZ: 18"
```

rqt_graph



launch file

The screenshot shows a terminal window with several tabs open, displaying ROS 2 launch configuration code. The code defines two nodes: 'talker' and 'listener1'. The 'talker' node is a Node package assigned to port 666610840, with a name of 'talker', output to 'screen', and remappings for '/gossip' to '/assignment5'. It also has parameters for 'who' (set to 'myROS'), 'speaking' (set to 'say'), and 'spk_msg' (set to 'y so EZ'). The 'listener1' node is a Node package assigned to port 666610840, with a name of 'listener1', output to 'screen', and remappings for '/gossip' to '/assignment5'. It also has parameters for 'who' (set to 'myROS'), 'speaking' (set to 'say'), and 'spk_msg' (set to 'y so EZ'). The code then adds actions for both nodes and generates a launch description if the name is 'main'. The terminal window also shows other tabs for setup scripts, package XML, and license files.

```
File Edit Selection View Go Run Terminal Help Jan 6 14:03
... setup.py U whisper_666610840.py U setup.cfg U package.xml U ros_name_sensei_ws C LICENSE U name_sensei.launch.py U D BLACKBOX D+ DMT D+ D+
EXPLORER
... setup.py U whisper_666610840 > launch.launch U ros_name_sensei.launchpy ...
src\assignment5_666610840> launch.launch U
1 from launch import LaunchDescription
2 from launch.actions import Node
3
4 def generate_launch_description():
5     ld = LaunchDescription()
6
7         talker = Node(
8             package='assignment5_666610840',
9             executable='talker',
10            name='talker',
11            output='screen',
12            remappings=[
13                ('/gossip', '/assignment5'),
14            ],
15            parameters=[
16                {'who': 'myROS',
17                 'speaking': 'say',
18                 'spk_msg': 'y so EZ'},
19            ]
20        )
21
22        listener1 = Node(
23             package='assignment5_666610840',
24             executable='listener1',
25            name='listener1',
26            output='screen',
27            remappings=[
28                ('/gossip', '/assignment5'),
29            ],
30            parameters=[
31                {'who': 'myROS',
32                 'speaking': 'say',
33                 'spk_msg': 'y so EZ'},
34            ]
35        )
36
37        id.add_action(talker)
38        id.add_action(listener1)
39        id.add_action(listener2)
40
41    return id
42
43 if __name__ == '__main__':
44     generate_launch_description()
45
46 how_to_run.txt
47 README.md
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setup.py