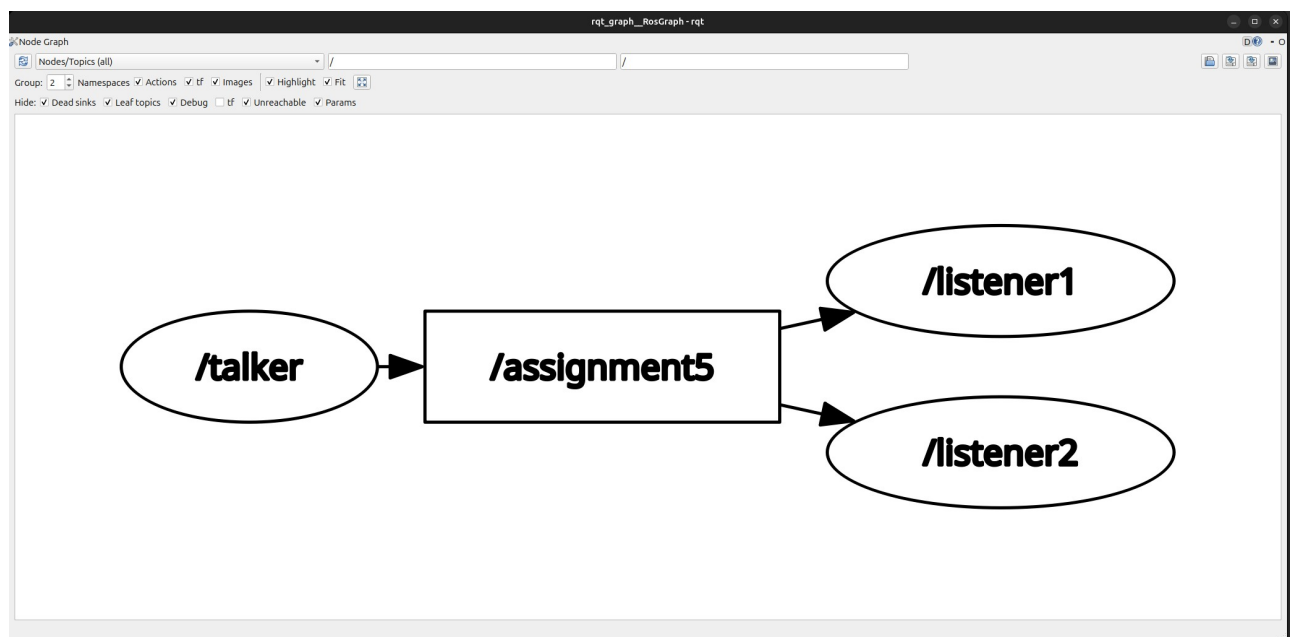


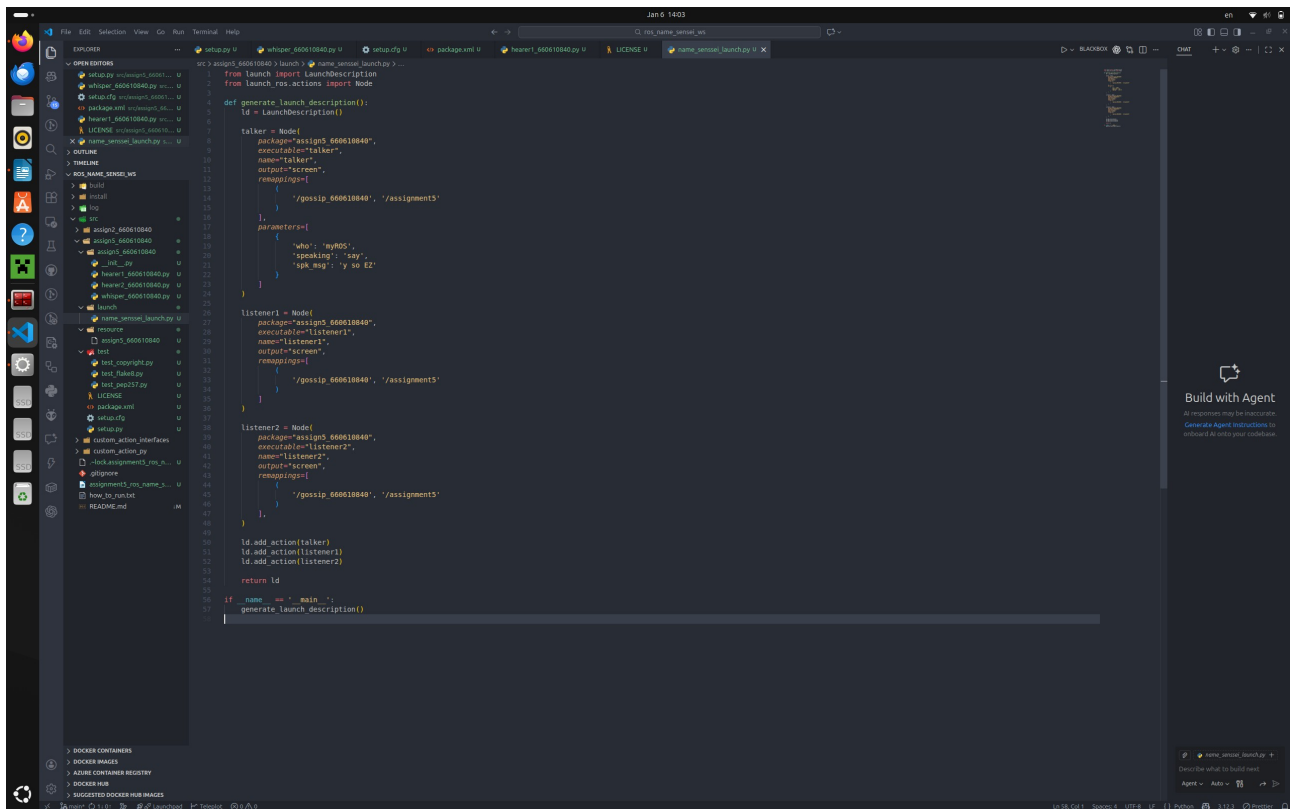
## Run in terminal

```
manna@mannaja: ~/study/ros_name_sensei_ws
p_660610840:=/assignment5'].
manna@mannaja:~/study/ros_name_sensei_ws$ ros2 launch assign5_660610840 name_sensei_launch.py
[INFO] [launch]: All log files can be found below /home/manna/.ros/log/2026-01-06-14-02-19-216602-manna-17708
[INFO] [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] [1767682944.600990601] [listener1]: SUB1 get: "y so EZ: 18"
```

## rqt\_graph

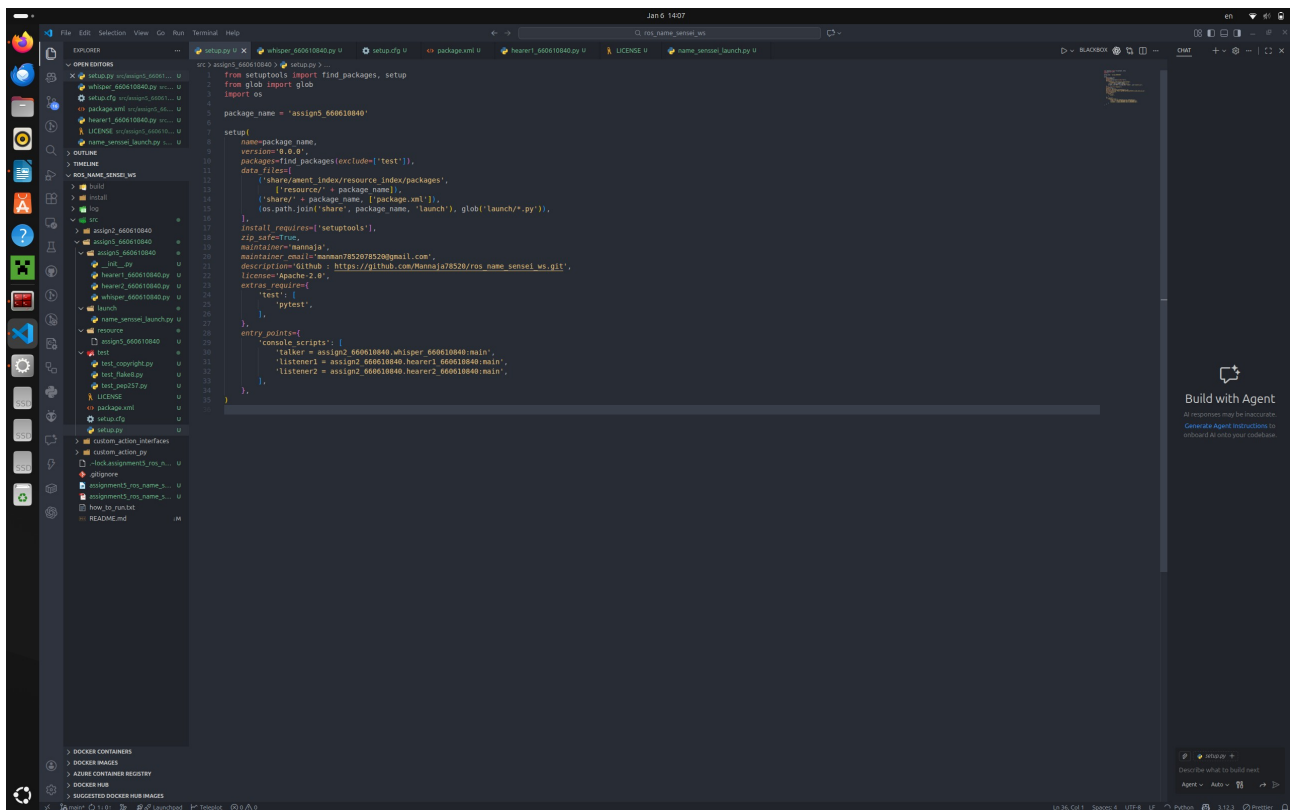


# launch file



```
1 from launch import LaunchDescription
2 from launch_ros.actions import Node
3
4 def generate_launch_description():
5     ld = LaunchDescription()
6
7     talker = Node(
8         package='assign5_660610840',
9         executable='talker',
10        name='talker',
11        output='screen',
12        remappings=[
13            ('/gossip_660610840', '/assignments')
14        ],
15        parameters=[
16            {
17                'who': 'MyROS',
18                'speaking': 'say',
19                'spk msg': 'y so EZ'
20            }
21        ],
22    )
23
24     listener1 = Node(
25         package='assign5_660610840',
26         executable='listener1',
27         name='listener1',
28         output='screen',
29         remappings=[
30             ('/gossip_660610840', '/assignments')
31         ],
32     )
33
34     listener2 = Node(
35         package='assign5_660610840',
36         executable='listener2',
37         name='listener2',
38         output='screen',
39         remappings=[
40             ('/gossip_660610840', '/assignments')
41         ],
42     )
43
44     ld.add_action(talker)
45     ld.add_action(listener1)
46     ld.add_action(listener2)
47
48     return ld
49
50 if __name__ == '__main__':
51     generate_launch_description()
```

# setup.py



```
1 from setuptools import find_packages, setup
2 from glob import glob
3
4 package_name = 'assign5_660610840'
5
6 setup(
7     name=package_name,
8     version='0.0.0',
9     packages=find_packages(exclude=['test']),
10    data_files=[
11        ('share/ament_index/resource_index/packages',
12         [resource('package_name')]),
13        ('share/' + package_name, ['package.xml']),
14        (os.path.join('share', package_name, 'launch'), glob('launch/*.py')),
15    ],
16    install_requires=['setuptools'],
17    zip_safe=True,
18    maintainer='MamaJa',
19    maintainer_email='Maman782307823@gmail.com',
20    description='Github: https://github.com/MamaJa78320/ros_name_sensei_ws.git',
21    license='Apache 2.0',
22    extras_require={
23        'test': [
24            'pytest',
25        ],
26    },
27    entry_points={
28        'console_scripts': [
29            'talker = assign5_660610840.whisper_660610840:main',
30            'listener1 = assign2_660610840.hearer1_660610840:main',
31            'listener2 = assign2_660610840.hearer2_660610840:main',
32        ],
33    },
34)
```