

Twá subscriber node

The screenshot shows a code editor interface with an 'EXPLORER' view on the left and three tabs of code on the right.

EXPLORER View:

- OPEN EDITORS:**
 - header1_660610840.py
 - LICENSE
 - name_sensei_launch.py
 - setup.py
 - setup.cfg
 - package.xml
 - LICENSE
 - assign6_660610840
 - name_sensei_launch.py
 - lidar_listener.py
 - __init__.py
- OUTLINE**
- TIMELINE**
- ROS_NAME_SENSEI_WS**
 - build
 - install
 - log
 - src**
 - assign2_660610840
 - __init__.py
 - header1_660610840.py
 - header2_660610840.py
 - whisper_660610840.py
 - resource
 - test
 - LICENSE
 - package.xml
 - setup.cfg
 - setup.py
 - assign5_660610840
 - __init__.py
 - lidar_listener.py
 - assign6_660610840
 - __init__.py
 - lidar_listener.py
 - launch
 - name_sensei_launch.py
 - resource
 - assign6_660610840
 - LICENSE
 - package.xml
 - setup.cfg
 - setup.py
 - custom_action_interfaces
 - custom_action_py
 - slidar_ros2
 - .gitignore
 - assignment5_ros_name_s...
 - assignment5_ros_name_s...
 - how_to_run.txt
 - README.md

terminal ຕອນຮັບ ເວິພາະ node

```
[rosrun]: interrupt  
mannaja@mannaja:~/study/ros_name_sensei_ws$ ros2 run assign6_660610840 lidar_listener  
[INFO] [1767942683.663622859] [lidar_scan_660610840]: LIDAR SCAN DATA:  
angle minimum: -3.1415927410125732  
angle maximum: 3.1415927410125732  
range minimum: 0.05000000074505806  
range maximum: 25.0  
Average distance (0° ± 5°): 0.436 m  
[INFO] [1767942683.664452825] [lidar_scan_660610840]: LIDAR SCAN DATA:  
angle minimum: -3.1415927410125732  
angle maximum: 3.1415927410125732  
range minimum: 0.05000000074505806  
range maximum: 25.0  
Average distance (0° ± 5°): 0.436 m  
[INFO] [1767942683.665043829] [lidar_scan_660610840]: LIDAR SCAN DATA:  
angle minimum: -3.1415927410125732  
angle maximum: 3.1415927410125732  
range minimum: 0.05000000074505806  
range maximum: 25.0  
Average distance (0° ± 5°): 0.435 m  
[INFO] [1767942683.665671642] [lidar_scan_660610840]: LIDAR SCAN DATA:  
angle minimum: -3.1415927410125732  
angle maximum: 3.1415927410125732  
range minimum: 0.05000000074505806  
range maximum: 25.0  
Average distance (0° ± 5°): 0.156 m  
[INFO] [1767942683.666244116] [lidar_scan_660610840]: LIDAR SCAN DATA:  
angle minimum: -3.1415927410125732  
angle maximum: 3.1415927410125732  
range minimum: 0.05000000074505806  
range maximum: 25.0  
Average distance (0° ± 5°): 0.156 m  
[INFO] [1767942683.666798619] [lidar_scan_660610840]: LIDAR SCAN DATA:  
angle minimum: -3.1415927410125732  
angle maximum: 3.1415927410125732  
range minimum: 0.05000000074505806  
range maximum: 25.0  
Average distance (0° ± 5°): 0.156 m  
[INFO] [1767942683.685643776] [lidar_scan_660610840]: LIDAR SCAN DATA:  
angle minimum: -3.1415927410125732  
angle maximum: 3.1415927410125732  
range minimum: 0.05000000074505806  
range maximum: 25.0  
Average distance (0° ± 5°): 0.156 m  
[INFO] [1767942683.765258392] [lidar_scan_660610840]: LIDAR SCAN DATA:  
angle minimum: -3.1415927410125732  
angle maximum: 3.1415927410125732  
range minimum: 0.05000000074505806  
range maximum: 25.0  
Average distance (0° ± 5°): 0.171 m  
[INFO] [1767942683.844882043] [lidar_scan_660610840]: LIDAR SCAN DATA:  
angle minimum: -3.1415927410125732  
mannaja@mannaja:~/study/ros_name_sensei_ws$ ros2 launch sllidar_ros2 sllidar_a3.launch.py  
[INFO] [launch]: All log files can be found below /home/mannaja/.ros/log/2026-01-09-14-10-56-041589-mannaja-26046  
[INFO] [launch]: Default logging verbosity is set to INFO  
[INFO] [sllidar_node-1]: process started with pid [26049]  
[sllidar_node-1] [INFO] [1767942656.130365826] [sllidar_node]: SLLidar running on ROS2 package SLLidar.ROS2 SDK Version:1.0.1, SLLIDAR SDK Version:2.1.0  
[sllidar_node-1] [INFO] [1767942656.136776698] [sllidar_node]: SLLidar S/N: 9CC5ED93C0EA98C9A5E698F2091B4669  
[sllidar_node-1] [INFO] [1767942656.136802500] [sllidar_node]: Firmware Ver: 1.32  
[sllidar_node-1] [INFO] [1767942656.136806891] [sllidar_node]: Hardware Rev: 6  
[sllidar_node-1] [INFO] [1767942656.137794586] [sllidar_node]: SLLidar health status : 0  
[sllidar_node-1] [INFO] [1767942656.137805651] [sllidar_node]: SLLidar health status : OK.  
[sllidar_node-1] [INFO] [1767942656.345764928] [sllidar_node]: current scan mode: Sensitivity, sample rate: 16 Khz, max_distance: 25.0 m, scan frequency:10.0 Hz,
```

launch file

The screenshot shows the Visual Studio Code interface with the following details:

- EXPLORER View:** Displays the project structure under "ROS_NAME_SENSEI_WS". It includes sub-directories for "assign2_660610840", "assign5_660610840", and "assign6_660610840", each containing files like "LICENSE", "package.xml", "setup.cfg", and "setup.py". Other visible files include "hearer1_660610840.py", "lidar_listener.py", and "name_sensei_launch.py".
- OPEN EDITORS View:** Shows three open files:
 - `name_sensei_launch.py`: A Python script defining a launch description for a lidar listener.
 - `setup.py`: A setup script for the package.
 - `setup.cfg`: Configuration file for the package.
- Code Editor Content:** The code for `name_sensei_launch.py` is as follows:

```
src > assign6_660610840 > resource > launch > name_sensei_launch.py > ...
1   from launch import LaunchDescription
2   from launch_ros.actions import Node
3   from launch_ros.substitutions import FindPackageShare
4   from launch.substitutions import PathJoinSubstitution
5   from launch.launch_description_sources import PythonLaunchDescriptionSource
6   from launch.actions import IncludeLaunchDescription
7   from ament_index_python.packages import get_package_share_directory
8   import os
9
10 def generate_launch_description():
11     ld = LaunchDescription()
12
13     lidar_dir = get_package_share_directory('sllidar_ros2')
14
15     lidar_launch = IncludeLaunchDescription(
16         PythonLaunchDescriptionSource(
17             os.path.join(lidar_dir, 'launch', 'sllidar_a3_launch.py')
18         ),
19     )
20
21     lidar_listener = Node(
22         package="assign6_660610840",
23         executable="lidar_listener",
24         name="lidar_listener",
25         output="screen",
26     )
27
28     ld.add_action(lidar_listener)
29     ld.add_action(lidar_launch)
30
31     return ld
32
33 if __name__ == '__main__':
34     generate_launch_description()
```

terminal ຕອບຮູ່ launch file

```
mannaaja@mannaaja:~/study/ros_name_sensei_ws$ ^C
mannaaja@mannaaja:~/study/ros_name_sensei_ws$ ros2 launch assign6_660610840 name_sensei.launch.py
[INFO] [launch]: All log files can be found below /home/mannaaja/.ros/log/2026-01-09-14-09-16-825792-mannaaja-25859
[INFO] [launch]: Default logging verbosity is set to INFO
[INFO] [lidar_listener-1]: process started with pid [25862]
[INFO] [sllidar_node-2]: process started with pid [25863]
[sllidar_node-2] [INFO] [1767942556.916695521] [sllidar_node]: SLLidar running on ROS2 package SLLidar.ROS2 SDK Version:1.0.1, SLLIDAR SDK Version:2.1.0
[sllidar_node-2] [INFO] [1767942556.922115245] [sllidar_node]: SLLidar S/N: 9CC5ED93C0EA98C9A5E698F2091B4669
[sllidar_node-2] [INFO] [1767942556.922141100] [sllidar_node]: Firmware Ver: 1.32
[sllidar_node-2] [INFO] [1767942556.922145487] [sllidar_node]: Hardware Rev: 6
[sllidar_node-2] [INFO] [1767942556.922837345] [sllidar_node]: SLLidar health status : 0
[sllidar_node-2] [INFO] [1767942556.922851922] [sllidar_node]: SLLidar health status : OK.
[sllidar_node-2] [INFO] [1767942557.128498278] [sllidar_node]: current scan mode: Sensitivity, sample rate: 16 Khz, max_distance: 25.0 m, scan frequency:10.0 Hz,
[lidar_listener-1] [INFO] [1767942558.639334184] [lidar_listener]: LIDAR SCAN DATA:
[lidar_listener-1] angle minimum: -3.1415927410125732
[lidar_listener-1] angle maximum: 3.1415927410125732
[lidar_listener-1] range minimum: 0.05000000074505806
[lidar_listener-1] range maximum: 25.0
[lidar_listener-1] Average distance (0° ± 5°): 0.417 m
[lidar_listener-1] [INFO] [1767942558.736883831] [lidar_listener]: LIDAR SCAN DATA:
[lidar_listener-1] angle minimum: -3.1415927410125732
[lidar_listener-1] angle maximum: 3.1415927410125732
[lidar_listener-1] range minimum: 0.05000000074505806
[lidar_listener-1] range maximum: 25.0
[lidar_listener-1] Average distance (0° ± 5°): 0.417 m
[lidar_listener-1] [INFO] [1767942558.841197488] [lidar_listener]: LIDAR SCAN DATA:
[lidar_listener-1] angle minimum: -3.1415927410125732
[lidar_listener-1] angle maximum: 3.1415927410125732
[lidar_listener-1] range minimum: 0.05000000074505806
[lidar_listener-1] range maximum: 25.0
[lidar_listener-1] Average distance (0° ± 5°): 0.417 m
[lidar_listener-1] [INFO] [1767942558.939359019] [lidar_listener]: LIDAR SCAN DATA:
[lidar_listener-1] angle minimum: -3.1415927410125732
[lidar_listener-1] angle maximum: 3.1415927410125732
[lidar_listener-1] range minimum: 0.05000000074505806
[lidar_listener-1] range maximum: 25.0
[lidar_listener-1] Average distance (0° ± 5°): 0.417 m
[lidar_listener-1] [INFO] [1767942559.037618026] [lidar_listener]: LIDAR SCAN DATA:
[lidar_listener-1] angle minimum: -3.1415927410125732
[lidar_listener-1] angle maximum: 3.1415927410125732
[lidar_listener-1] range minimum: 0.05000000074505806
[lidar_listener-1] range maximum: 25.0
[lidar_listener-1] Average distance (0° ± 5°): 0.418 m
[lidar_listener-1] [INFO] [1767942559.135675691] [lidar_listener]: LIDAR SCAN DATA:
[lidar_listener-1] angle minimum: -3.1415927410125732
[lidar_listener-1] angle maximum: 3.1415927410125732
[lidar_listener-1] range minimum: 0.05000000074505806
[lidar_listener-1] range maximum: 25.0
[lidar_listener-1] Average distance (0° ± 5°): 0.418 m
[lidar_listener-1] [INFO] [1767942559.234182031] [lidar_listener]: LIDAR SCAN DATA:
[lidar_listener-1] angle minimum: -3.1415927410125732
[lidar_listener-1] angle maximum: 3.1415927410125732
[lidar_listener-1] range minimum: 0.05000000074505806
[lidar_listener-1] range maximum: 25.0
[lidar_listener-1] Average distance (0° ± 5°): 0.417 m
[lidar_listener-1] [INFO] [1767942559.326610065] [lidar_listener]: LIDAR SCAN DATA:
[lidar_listener-1] angle minimum: -3.1415927410125732
[lidar_listener-1] angle maximum: 3.1415927410125732
[lidar_listener-1] range minimum: 0.05000000074505806
[lidar_listener-1] range maximum: 25.0
[lidar_listener-1] Average distance (0° ± 5°): 0.417 m
[lidar_listener-1] [INFO] [1767942559.418227173] [lidar_listener]: LIDAR SCAN DATA:
[lidar_listener-1] angle minimum: -3.1415927410125732
[lidar_listener-1] angle maximum: 3.1415927410125732
[lidar_listener-1] range minimum: 0.05000000074505806
[lidar_listener-1] range maximum: 25.0
[lidar_listener-1] Average distance (0° ± 5°): 0.416 m
```