

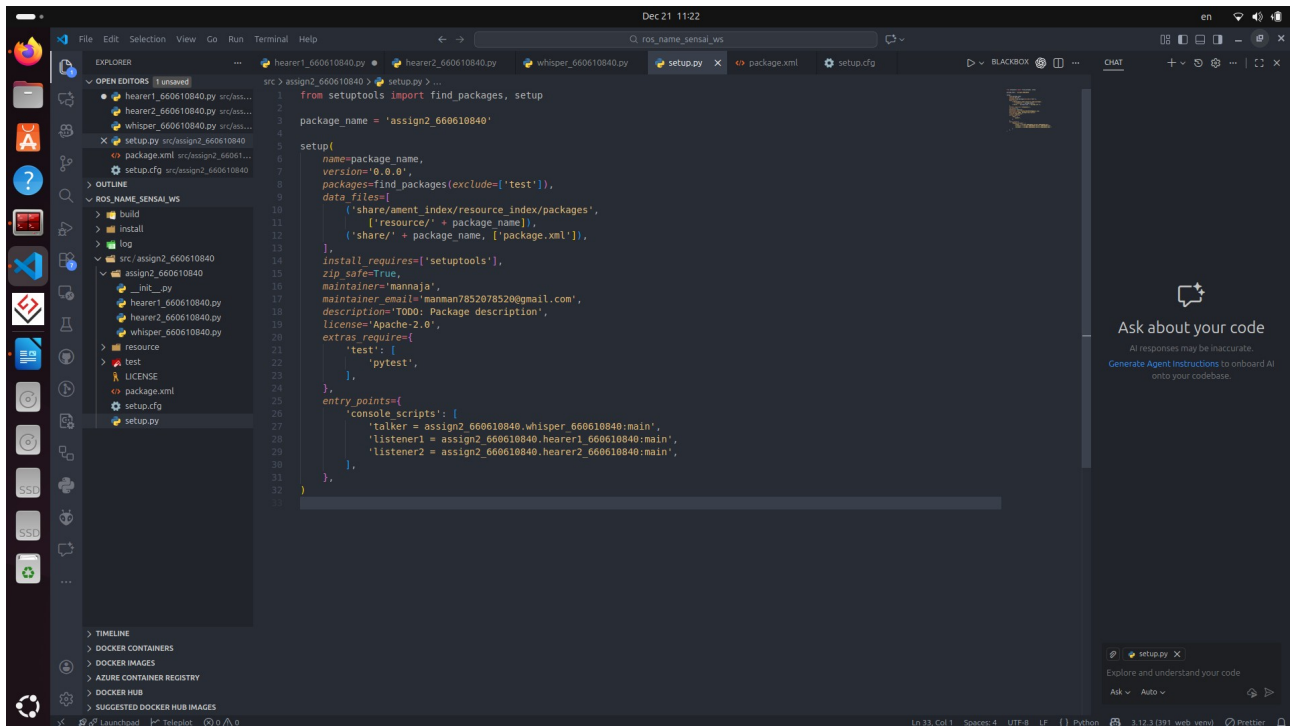
directory ของที่อยู่ไฟล์ source code

```
isai_ws/src/assign2_660610840/assign2_660610840
mannaia@mannaia: ~/study/ros_name_sensai_ws/src/assign2_660610840/assign2_660610840 79x17
(391_web_venv) mannaia@mannaia:~/study/ros_name_sensai_ws$ ls
build install log src
(391_web_venv) mannaia@mannaia:~/study/ros_name_sensai_ws$ cd src/assign2_660610840/
(391_web_venv) mannaia@mannaia:~/study/ros_name_sensai_ws/src/assign2_660610840$ ls
assign2_660610840 LICENSE package.xml resource setup.cfg setup.py test
(391_web_venv) mannaia@mannaia:~/study/ros_name_sensai_ws/src/assign2_660610840$ cd assign2_660610840/
(391_web_venv) mannaia@mannaia:~/study/ros_name_sensai_ws/src/assign2_660610840/assign2_660610840$ ls
hearer1_660610840.py hearer2_660610840.py __init__.py whisper_660610840.py
(391_web_venv) mannaia@mannaia:~/study/ros_name_sensai_ws/src/assign2_660610840/assign2_660610840$
```

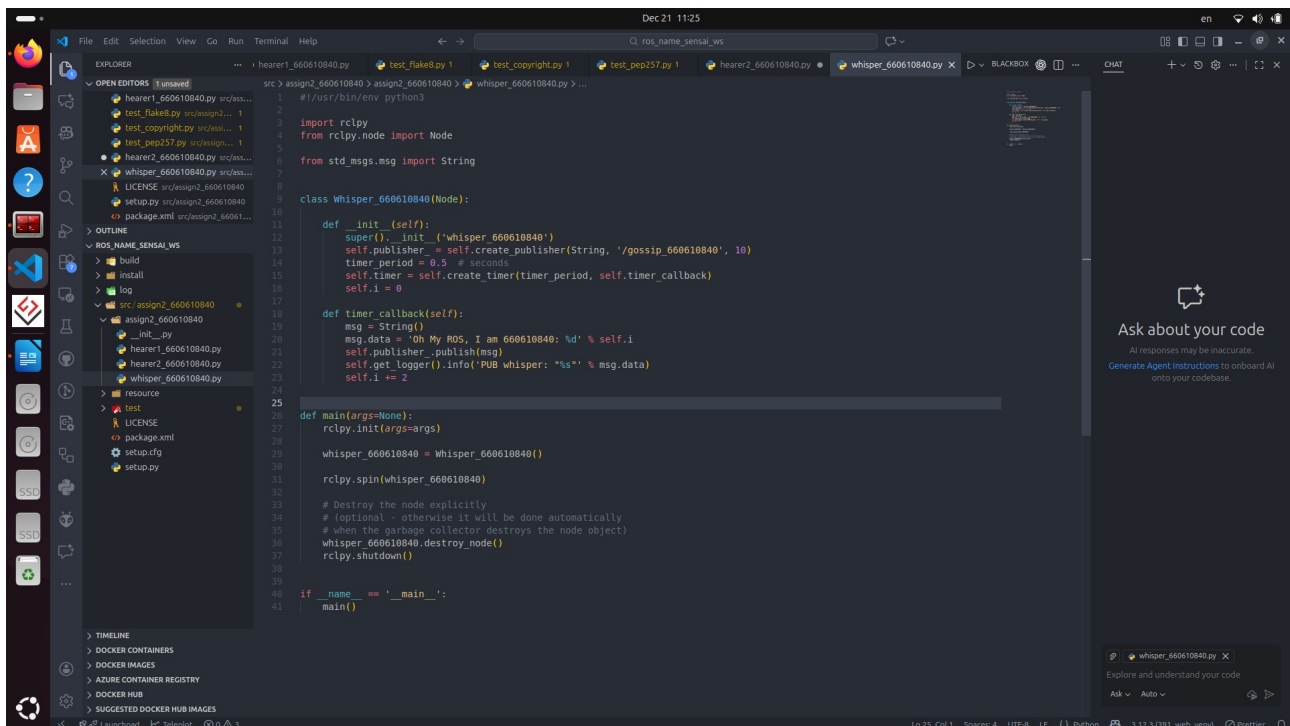
code ไฟล์ package.xml

```
Dec 21 11:21
ros_name_sensai_ws
package.xml
1 <?xml version="1.0"?>
2 <?xml-model href="http://download.ros.org/schema/package_format3.xsd" schematypens="http://www.w3.org/2001/XMLSchema"?>
3 <package format="3"?>
4   <name>assign2_660610840</name>
5   <version>0.0.0</version>
6   <description>T000: Package description</description>
7   <maintainer email="mannaia7852078520@gmail.com">mannaia</maintainer>
8   <license>Apache-2.0</license>
9
10  <exec_depend>roscpp</exec_depend>
11  <exec_depend>std_msgs</exec_depend>
12
13  <test_depend>ament_copyright</test_depend>
14  <test_depend>ament_flake8</test_depend>
15  <test_depend>ament_pep257</test_depend>
16  <test_depend>python3-pytest</test_depend>
17
18  <export>
19    <build_type>ament_python</build_type>
20  </export>
21 </package>
```

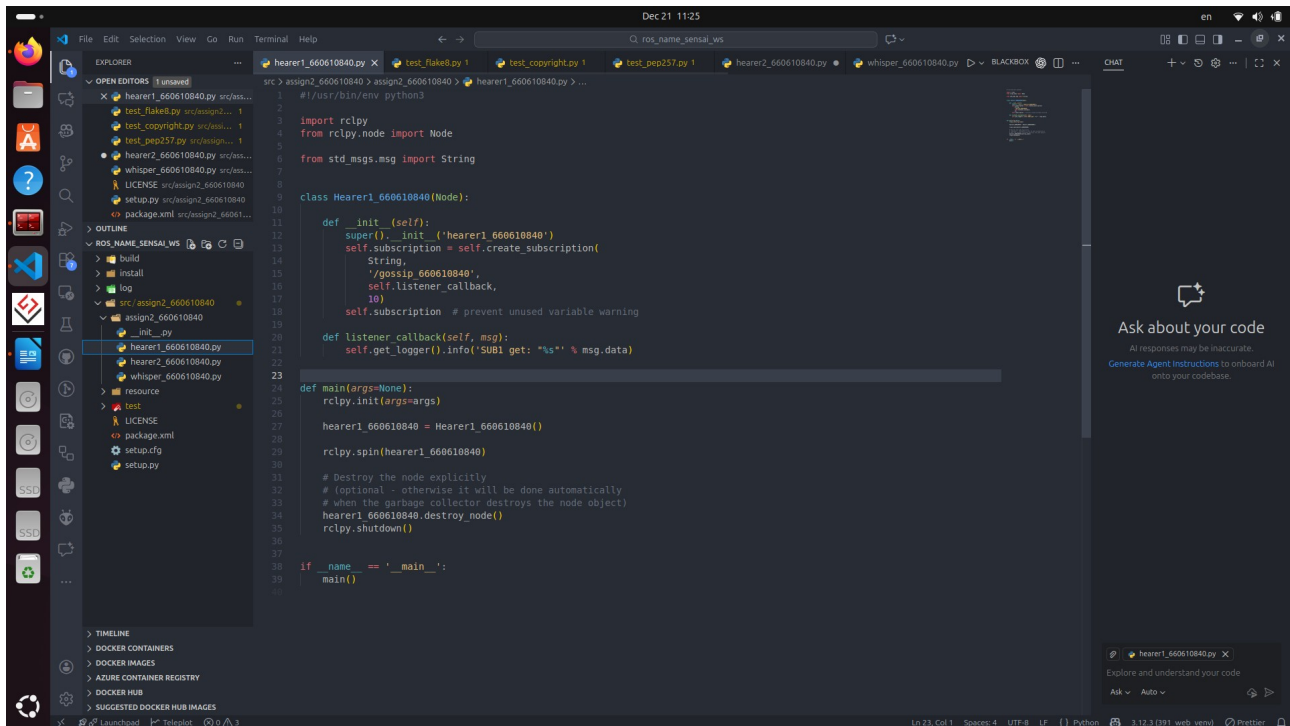
code ไฟล์ setup.py หรือ CmakeLists.txt



code ไฟล์ publisher

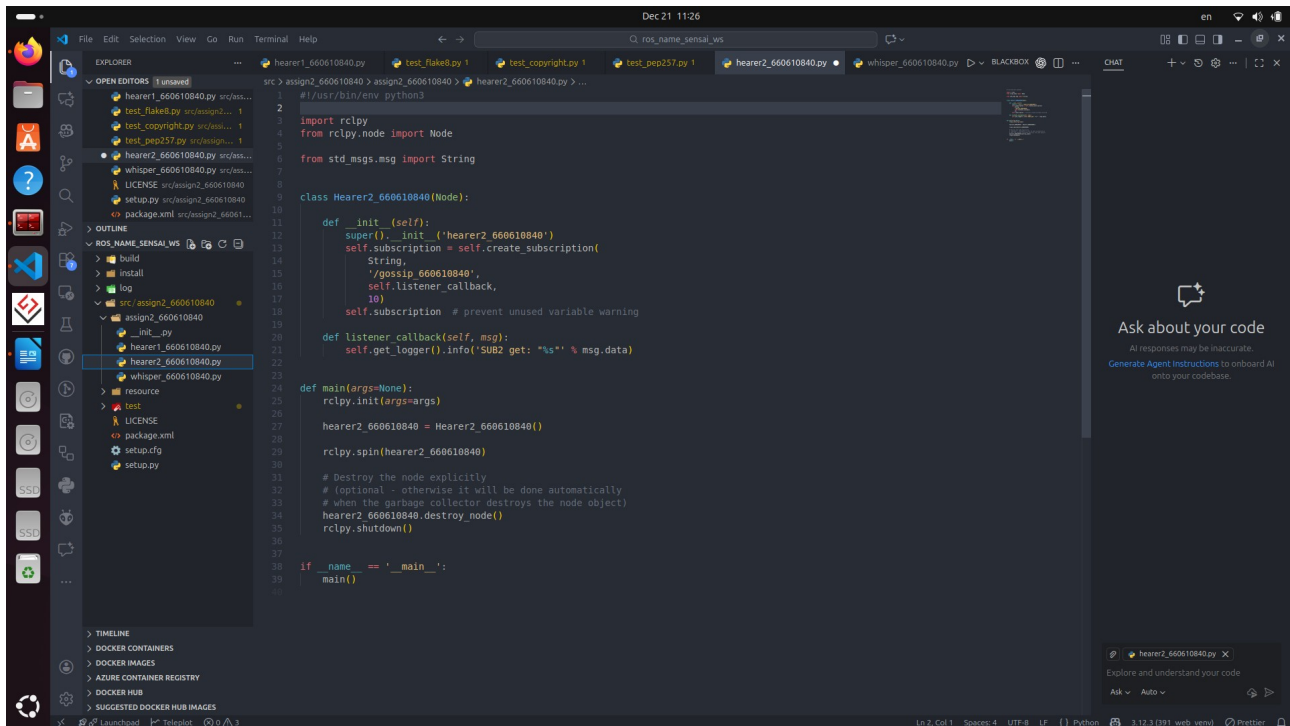


code Twā subscriber1



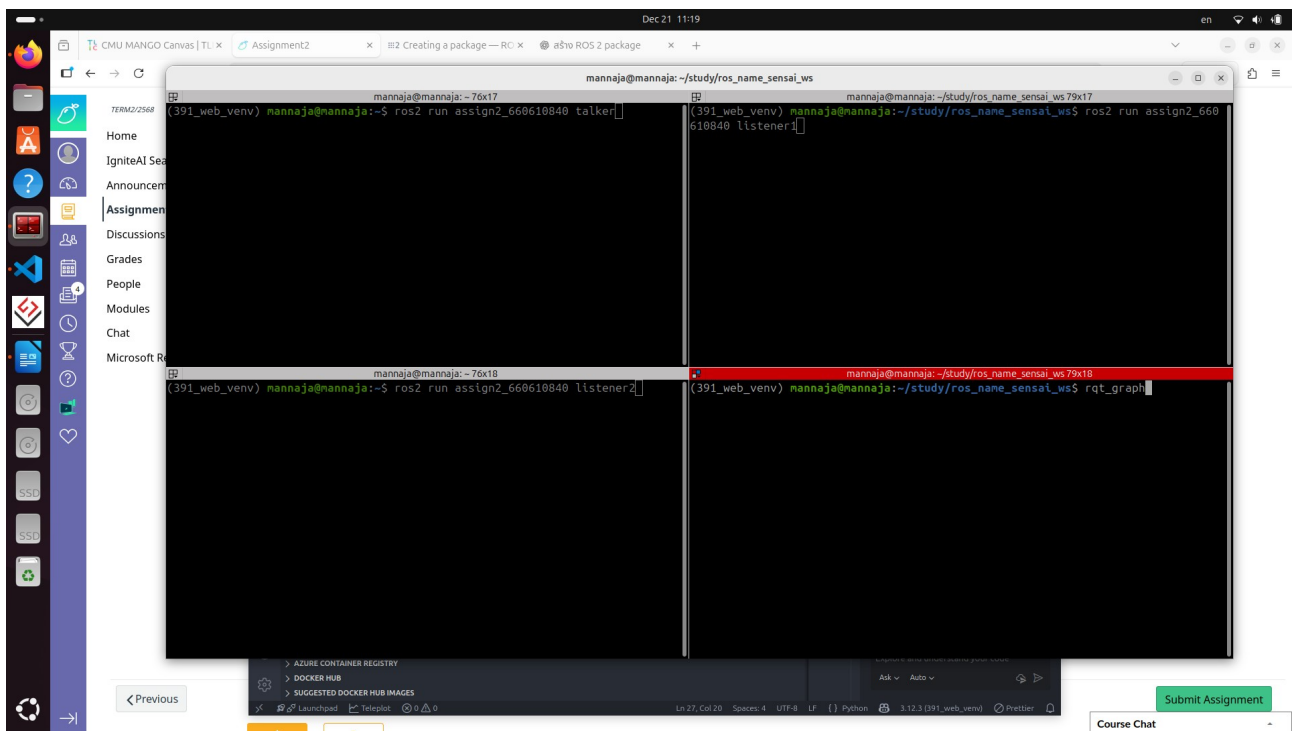
```
1 #!/usr/bin/env python3
2
3 import rclpy
4 from rclpy.node import Node
5
6 from std_msgs.msg import String
7
8
9 class Hearer1_660610840(Node):
10
11     def __init__(self):
12         super().__init__('hearer1_660610840')
13         self.subscription = self.create_subscription(
14             String,
15             '/gossip_660610840',
16             self.listener_callback,
17             10)
18         self.subscription # prevent unused variable warning
19
20     def listener_callback(self, msg):
21         self.get_logger().info('SUB1 get: "%s"' % msg.data)
22
23
24 def main(args=None):
25     rclpy.init(args=args)
26
27     hearer1_660610840 = Hearer1_660610840()
28
29     rclpy.spin(hearer1_660610840)
30
31     # Destroy the node explicitly
32     # (optional - otherwise it will be done automatically
33     # when the garbage collector destroys the node object)
34     hearer1_660610840.destroy_node()
35     rclpy.shutdown()
36
37
38 if __name__ == '__main__':
39     main()
40
```

code Twā subscriber2

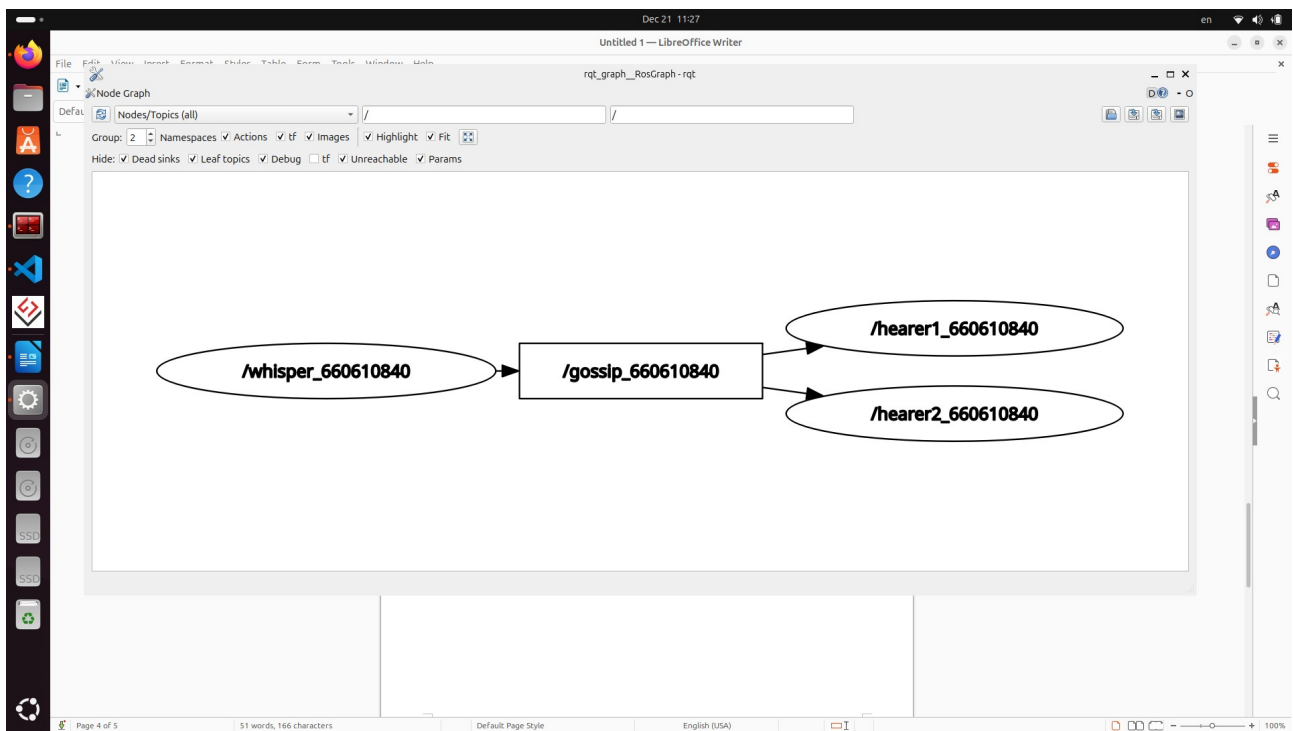


```
1 #!/usr/bin/env python3
2
3 import rclpy
4 from rclpy.node import Node
5
6 from std_msgs.msg import String
7
8
9 class Hearer2_660610840(Node):
10
11     def __init__(self):
12         super().__init__('hearer2_660610840')
13         self.subscription = self.create_subscription(
14             String,
15             '/gossip_660610840',
16             self.listener_callback,
17             10)
18         self.subscription # prevent unused variable warning
19
20     def listener_callback(self, msg):
21         self.get_logger().info('SUB2 get: "%s"' % msg.data)
22
23
24 def main(args=None):
25     rclpy.init(args=args)
26
27     hearer2_660610840 = Hearer2_660610840()
28
29     rclpy.spin(hearer2_660610840)
30
31     # Destroy the node explicitly
32     # (optional - otherwise it will be done automatically
33     # when the garbage collector destroys the node object)
34     hearer2_660610840.destroy_node()
35     rclpy.shutdown()
36
37
38 if __name__ == '__main__':
39     main()
40
```

ภาพก่อนจะ run



rqt_graph



terminals မဆက္က node

