**Hello ROS!**

In this short tutorial we will validate our ROS installations and begin to explore how the system works.

**Step 1. Install ROS.**

Follow the instructions here: <http://wiki.ros.org/ROS/Tutorials/InstallingandConfiguringROSEnvironment>

**Step 2. Install and run TurtleSim**.

1. Follow the tutorial here: http://wiki.ros.org/ROS/Tutorials/UnderstandingTopics (More information on turtle sim is here: <http://wiki.ros.org/turtlesim>
2. For Step 3, you will need to be able to run a TurtleSim with a default motion/velocity

**Step 3. Create a TurtleBabySitter**

1. First create your own subscriber node to report on a TurtleSims location. A starting place can be found here: <http://wiki.ros.org/ROS/Tutorials/WritingPublisherSubscriber%28python%29> . Validate this system by moving TurtleSim and demonstrating the location updates appropriately
2. Create a TurtleBabySitter Server to check if TurtleSim is within a rectangular region defined by the corners (float xupper, float yupper) and float (xlower, float ylower). Use the listener create in Step3a to perform this query. A starting place can be found here: <http://wiki.ros.org/ROS/Tutorials/WritingServiceClient%28python%29>.
3. Create a Client for TurtleBabySitter to query the TurtleBabySitter server. Validate the client by querying the TurtleBabySitter such that (a) TurtleSim is within the region and (b) TurtleSim is outside the region. A starting place can be found here: <http://wiki.ros.org/ROS/Tutorials/WritingServiceClient%28python%29>.