# ROS2 5,6
(Robot Operating System)

You are required to create a ROS2 package (ros2_project) that spawns 2 turtlesims and control one of them to reach the other, and whenever your controllable turtle reaches its goal you should kill the goal turtle, and spawn another one in a random position and go to it.

Hint: x and y limits of the random position to spawn the turtle are [1,10]

You will use the following :

1) The turtlesim_node from the turtlesim package
2) "turtle1/cmd_vel " ,"turtle1/pose" topics
3) "spawn","kill" services
4) make a control node and name it (control_node.py)
5) make a spawn node and name it (spawn_node.py)
6) make custom srv
7) make launch file that includes (turtlesim_node, control_node, spawn_node)

Instructors repo Link:

1- https://github.com/ahmedgharieb1
2- https://github.com/M-abdeen
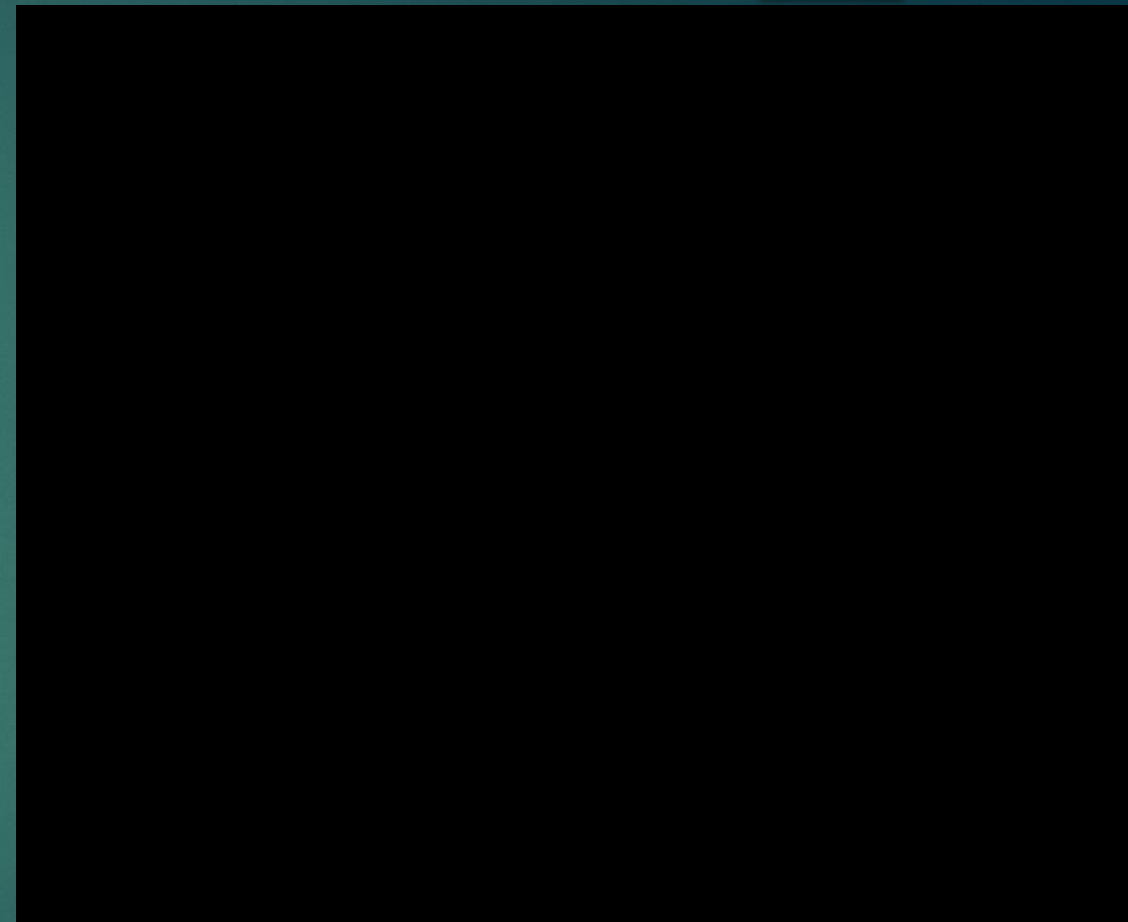
Material repo :
https://github.com/ahmedgharieb1/ITI_LSV_ROS2

Presentation Link:
https://docs.google.com/presentation/d/1DIPY0f9PwsUyCdCu_e1ouR1yikDMAClWeH
KN1df2qO0/edit#slide=id.gd124c8ff8e_0_0