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ROS2 LAB3

(*Robot Operating System*)

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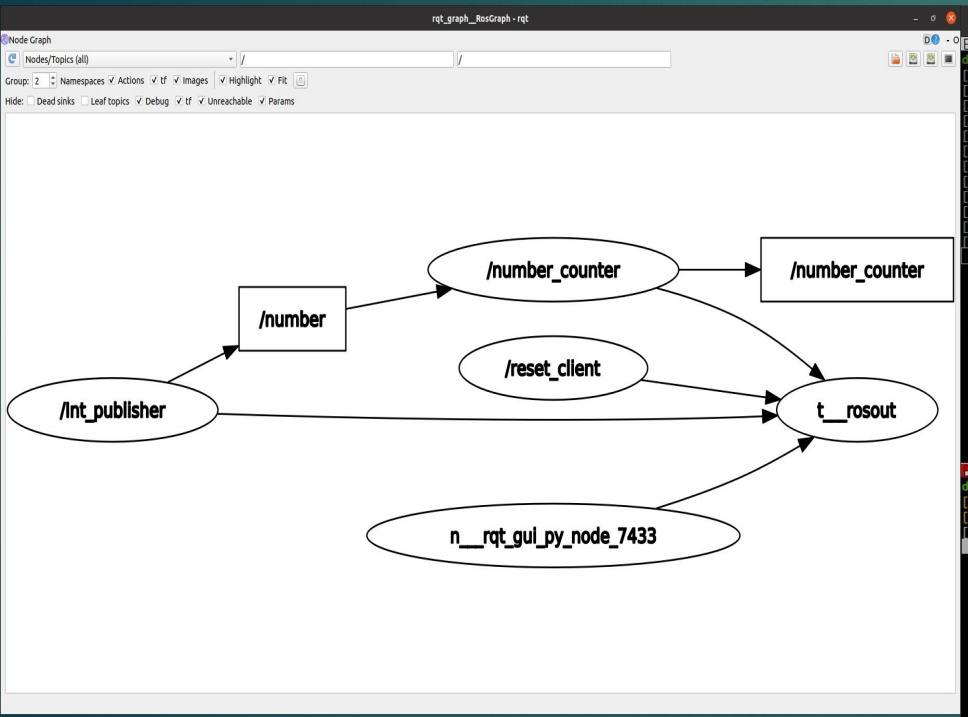
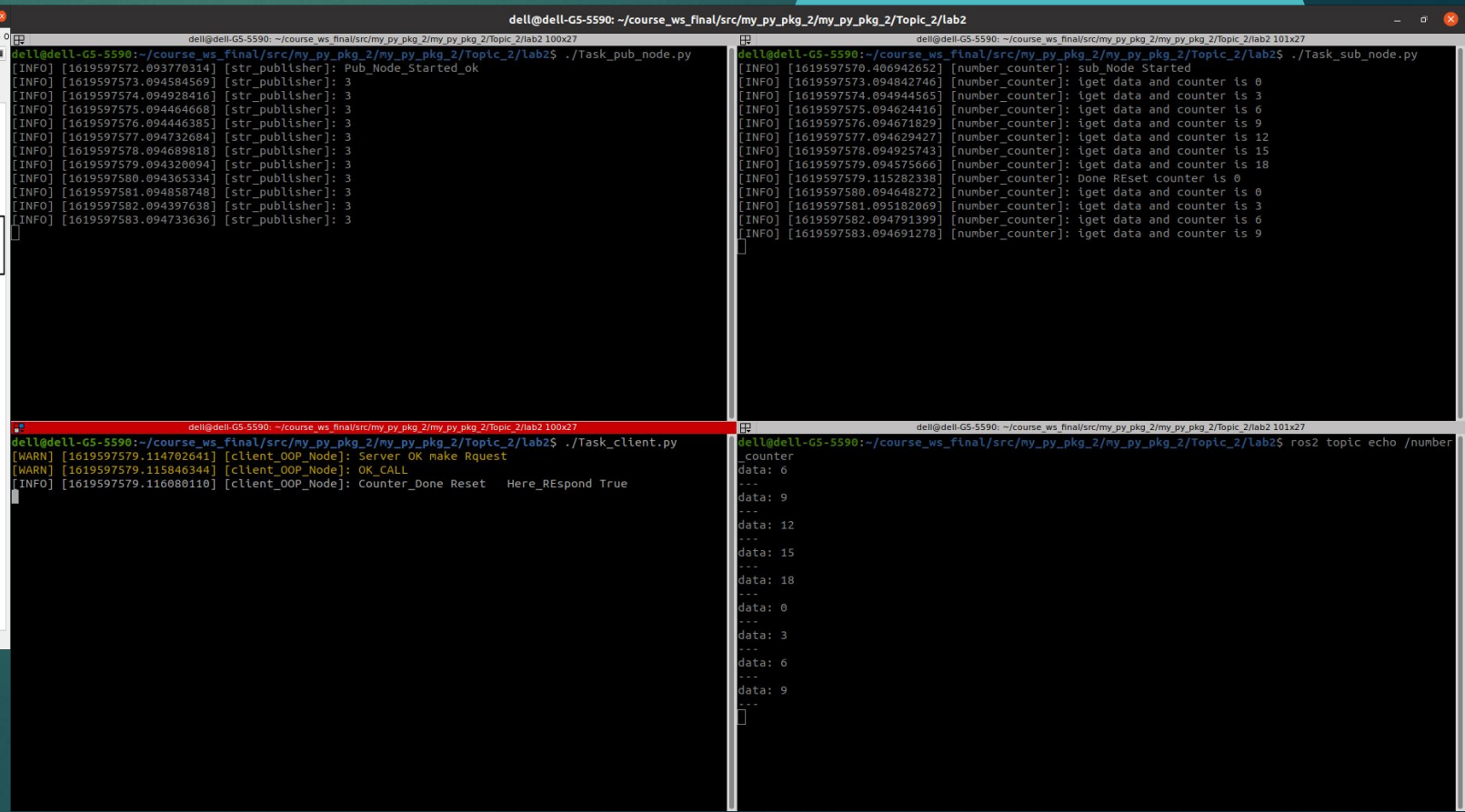
Make a ROS2 python package <iti_lab3> that includes 3 nodes (node1, node2, node3) as shown. node1 should publish a custom message formed of 2 variables: A string variable “<your name> is publishing: 5”, and an Int64 variable with a fixed value “5”. node2 should receive the custom msg, accumulate the Int64 variable into a counter, and then publish the accumulated counter, also the node should reset the accumulated counter using a custom service that would be called from node3, the service should have a boolean variable in the request and a string variable in the response. A single launch file should launch node1, and node2. show your rqt_graph as shown and save it as a png image.





Task 2: Deadline 4/5/2021 11:59 pm (bonus)
Make a ROS2 python node that publish a geometry_msgs/Twist on the topic /turtle1/cmd_vel to move turtlesim in the following sequence:
1- Linear x velocity for 1 second
2- Linear x velocity, and angular z velocity for 1 second
3- Angular z velocity for 1 second

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Instructors repo Link:

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

Material repo :
https://github.com/ahmedgharieb1/ITI_LSV_ROS2