tekomoro

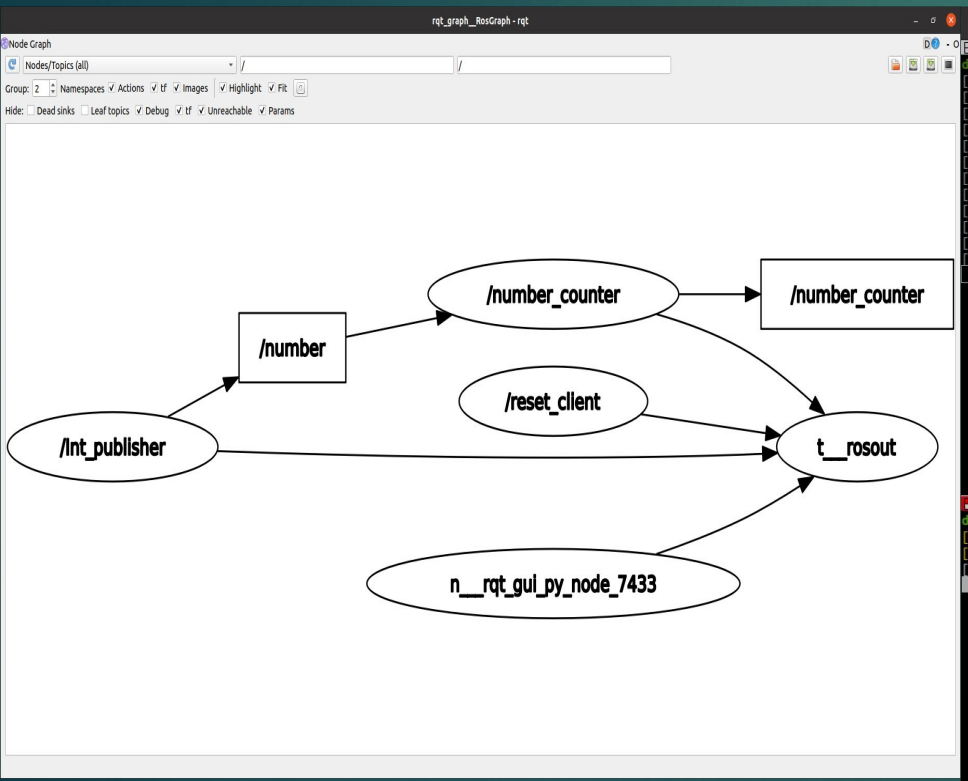
ROS2 LAB2

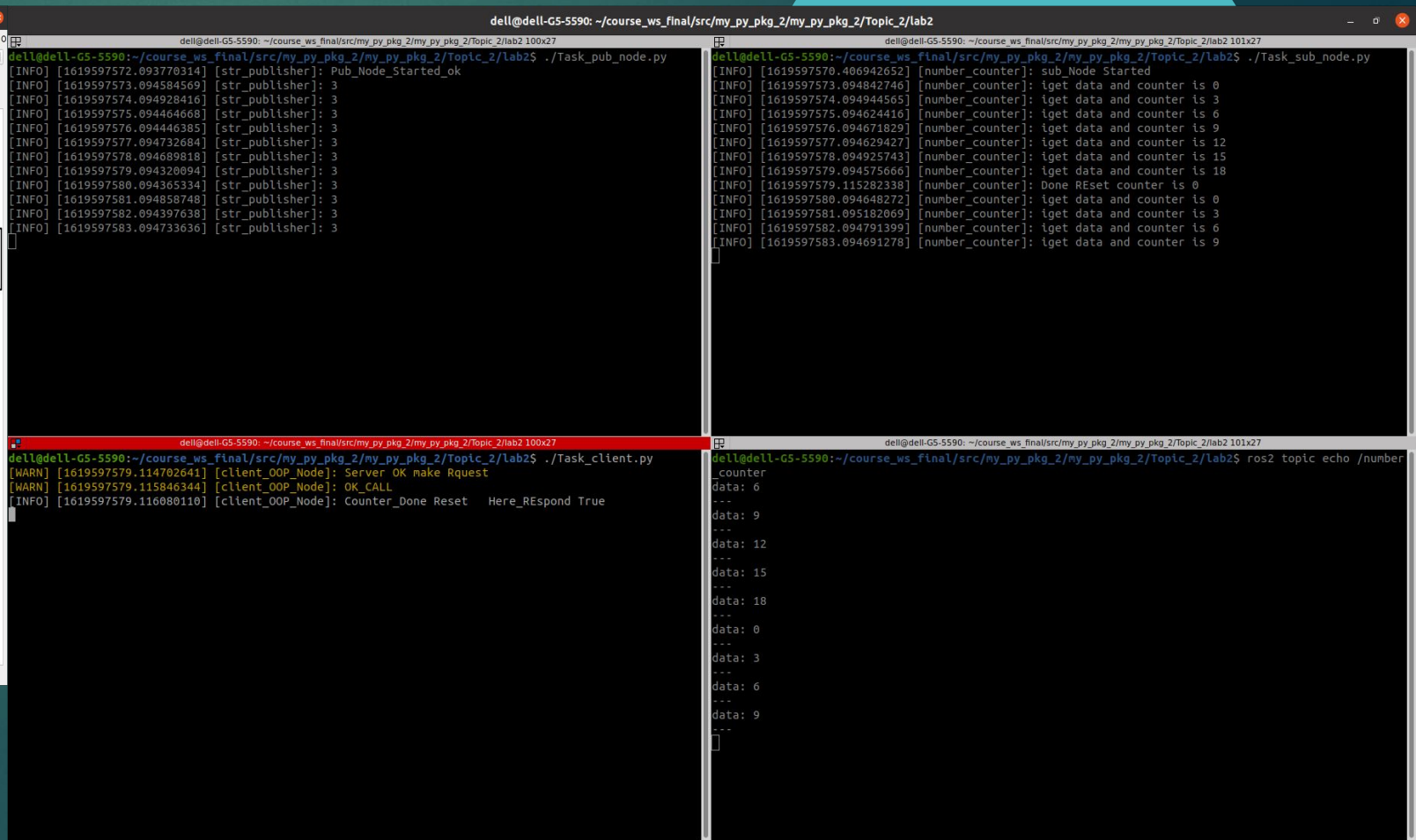
(*Robot Operating System*)

tekomoro

Make ros2 python package <iti_lab2> include 3 node (node1,node2,node3) as shown ,node1 publish Int64 msg with a fixed value (“5”) ,node2 receive Int64 msg and accumulate it, publish the accumulated counter and reset the accumulated counter using client node (node3) when it called. show your rqt_graph as shown save it as png image.

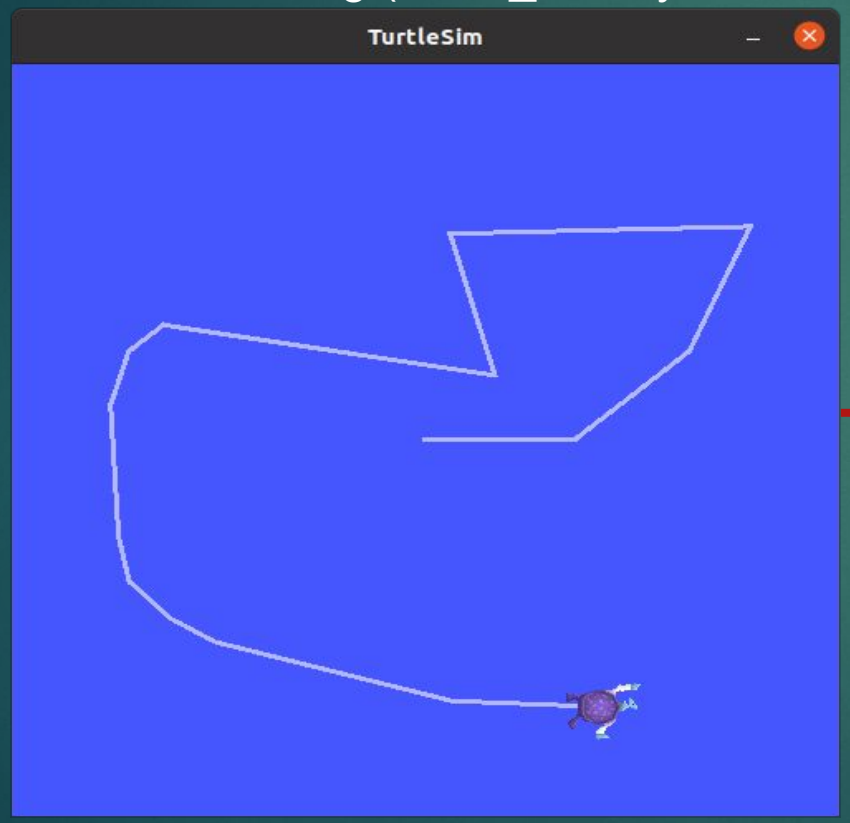
hint : use srv type : `example_interfaces/srv/SetBool`



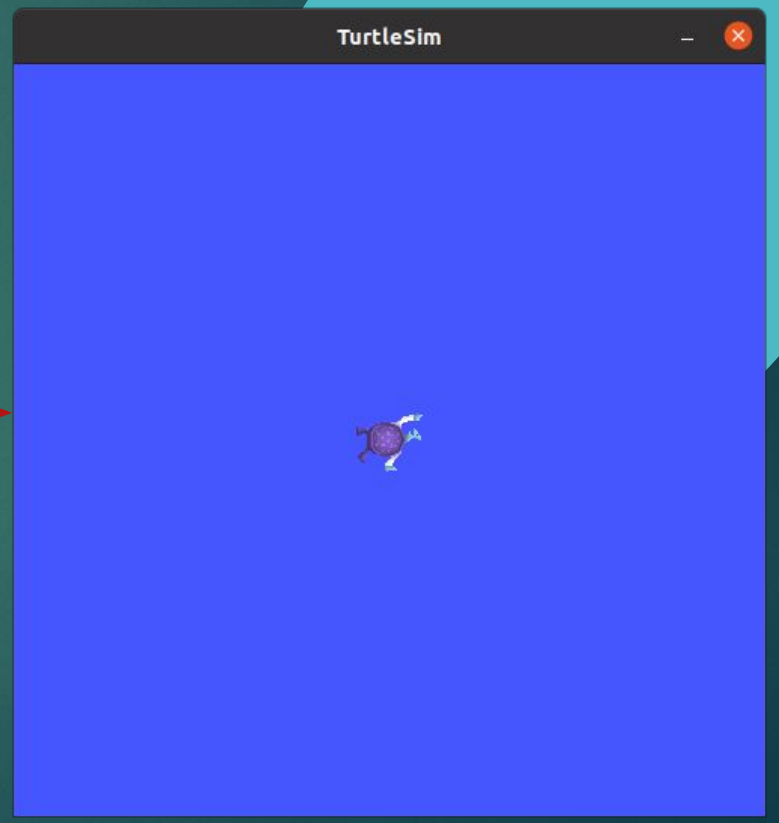


- In iti_lab2 package

1- make client Node to reset the turtle in turtlesim package
2- run turtlesim node
3- run turtlesim telop_key node to move the turtle
4- call reset service using (client_node you made)



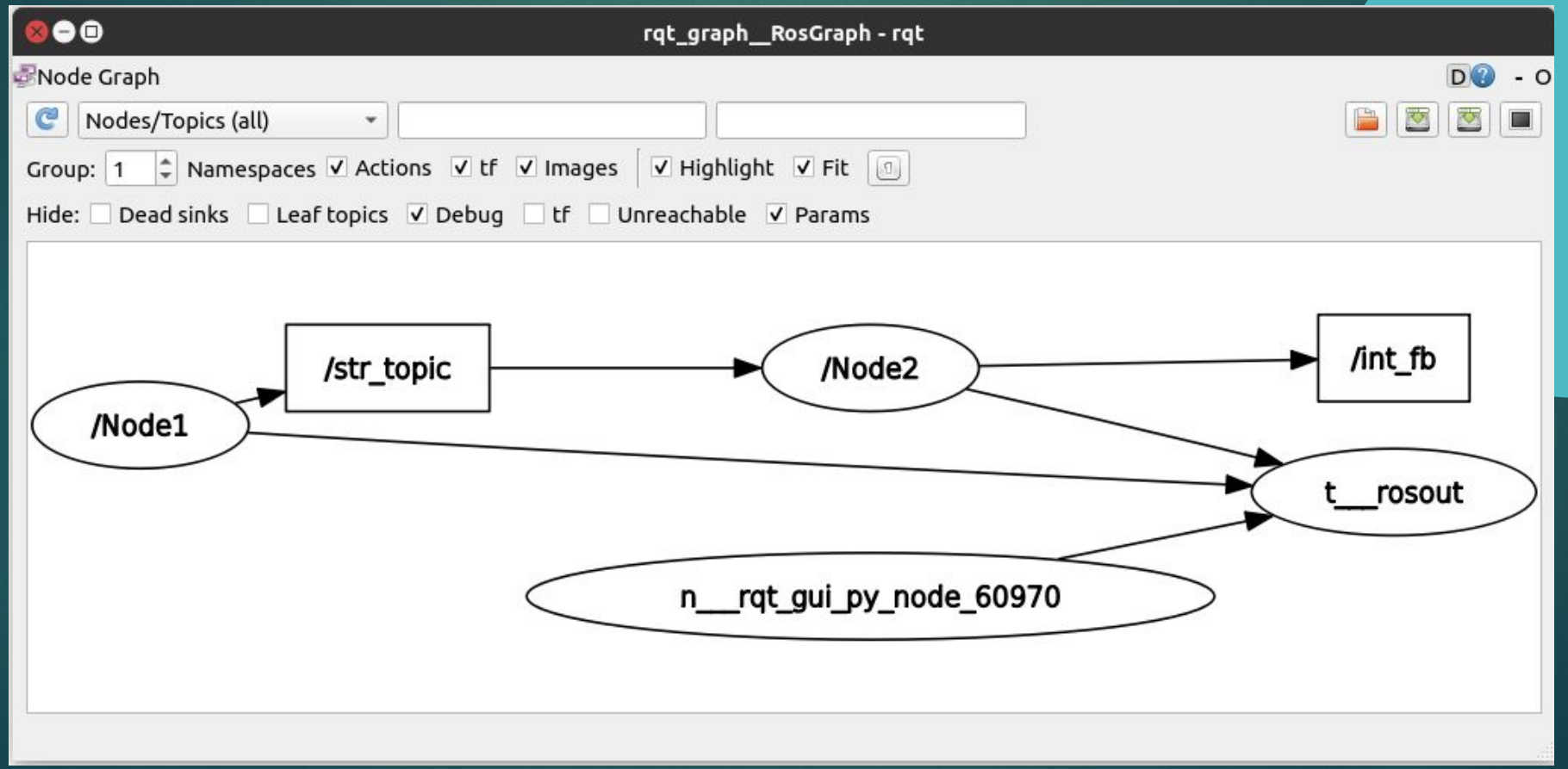
after call reset service



tekomoro

Task 3 : Deadline Friday 30/4 11:59 pm

Make a ROS2 c++ package <cpp_lab2> that includes 2 nodes (Node1,Node2) as shown ,node1 should publish a string msg (“ <your name> is publishing: <counter>”) counter should start with 0 and increment once every 1 second, node2 should receive the string msg, and publish the counter in a separate message. Show your rqt_graph as shown, save it as a png image.



tekomoro

Instructors repo Link:

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

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