#!usr/bin/env python

#Made using the ROS WIki Tutorial

import rospy

from std\_msgs.msg import String

#function to say what message we have received from the publisher node

def callback(message):

#In the rospy log print what we’ve heard, and also print on Python

rospy.loginfo(rospy.get\_caller\_id() + “I heard %s“, message.data)

print(rospy.get\_caller\_id() + “I heard %s“, message.data)

#Main listener node

def listener\_Node():

#Initialize the node and make it anonymous so that is has a unique name so we can run multiple instances of the same program

rospy.init\_node(‘listener’, anonymous=True)

#Designate the node as a subscriber to the publisher node ‘chatter’, and run the function callback as soon as we get a message in the form of a string

rospy.Subscriber(“chatter”, String, callback)

#Don’t exit until this node stops

rospy.spin()

#Start the function when the program runs

if \_\_name\_\_ == ‘\_\_main\_\_’:

listener\_Node()