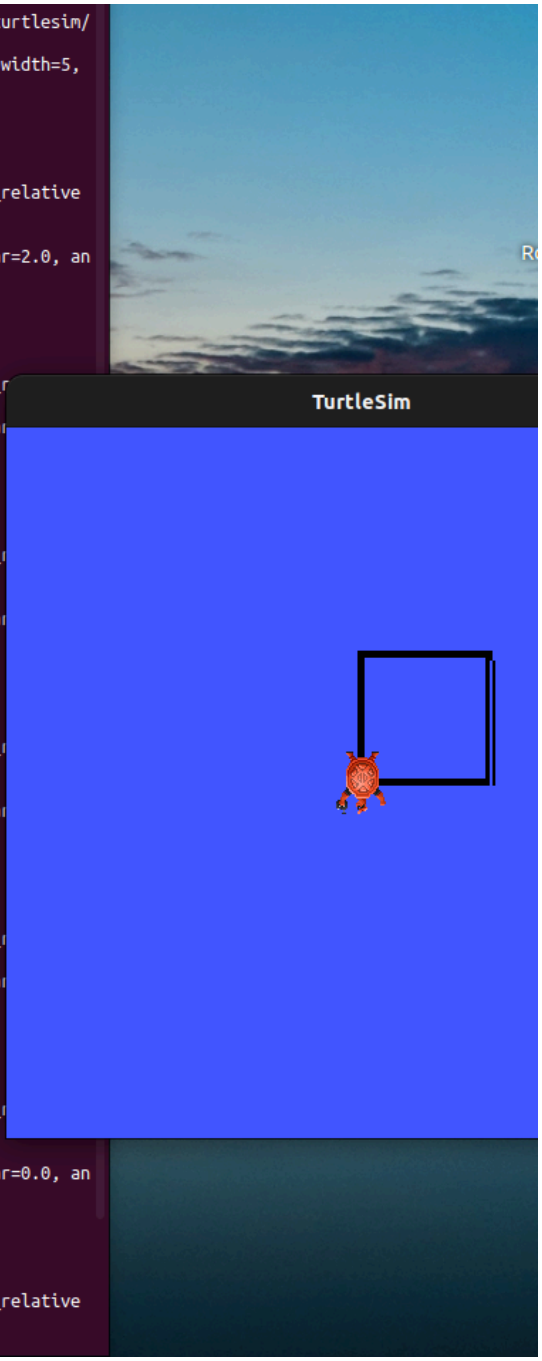
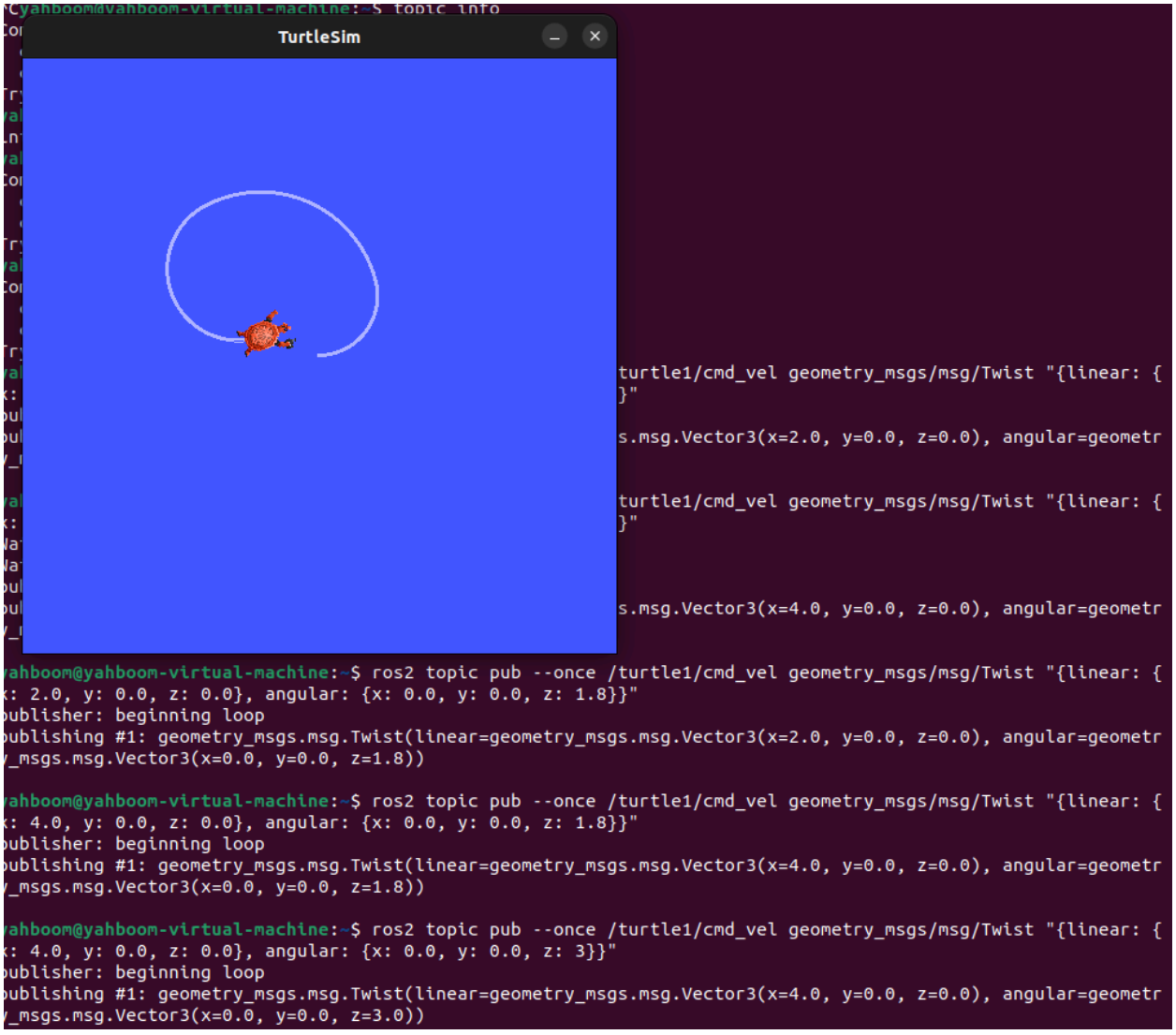
Here are the commands and output for creating a black square using turtlesim.

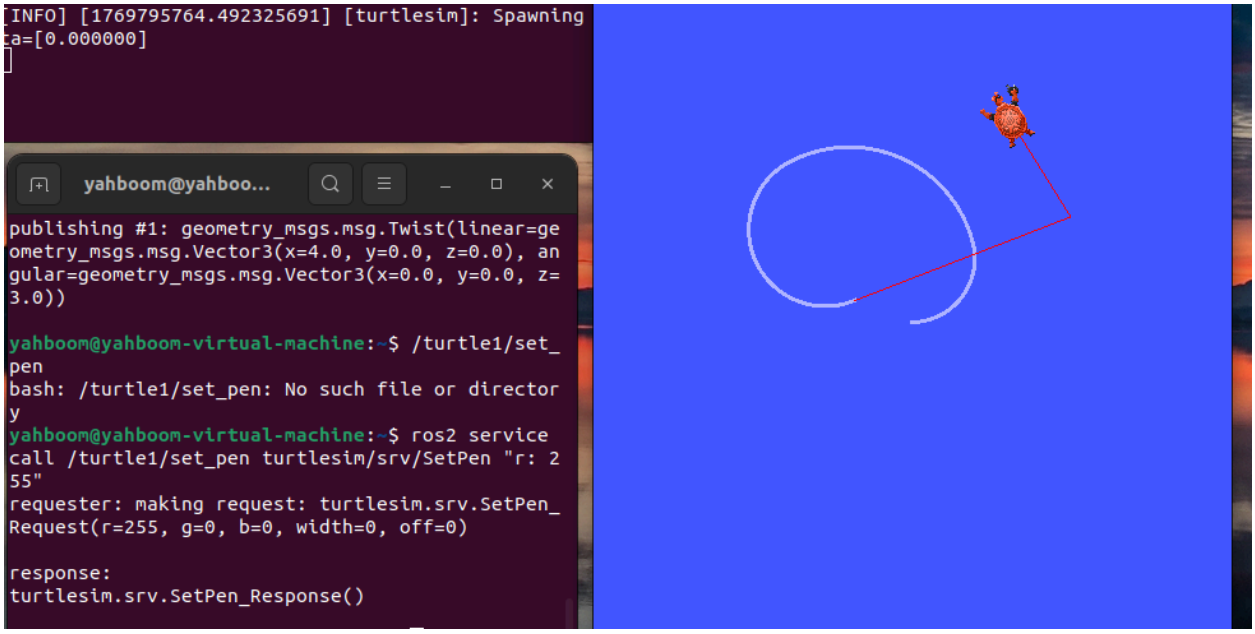
```
yahboom@yahboom-virtual-machine:~$ ros2 service call /turtle1/set_pen turtlesim/
srv/SetPen "{r: 0, g: 0, b: 0, width: 5}"
requester: making request: turtlesim.srv.SetPen_Request(r=0, g=0, b=0, width=5,
off=0)

response:
turtlesim.srv.SetPen_Response()

yahboom@yahboom-virtual-machine:~$ ros2 service call /turtle1/teleport_relative
turtlesim/srv/TeleportRelative "{linear: 2.0, angular: 0.0}"
waiting for service to become available...
requester: making request: turtlesim.srv.TeleportRelative_Request(linear=2.0, an
gular=0.0)

response:
turtlesim.srv.TeleportRelative_Response()

yahboom@yahboom-virtual-machine:~$ ros2 service call /turtle1/teleport_r
turtlesim/srv/TeleportRelative "{linear: 0.0, angular: 1.57079632679}"
requester: making request: turtlesim.srv.TeleportRelative_Request(linea
gular=1.57079632679)

response:
turtlesim.srv.TeleportRelative_Response()

yahboom@yahboom-virtual-machine:~$ ros2 service call /turtle1/teleport_
turtlesim/srv/TeleportRelative "{linear: 2.0, angular: 0.0}"
waiting for service to become available...
requester: making request: turtlesim.srv.TeleportRelative_Request(linea
gular=0.0)

response:
turtlesim.srv.TeleportRelative_Response()

yahboom@yahboom-virtual-machine:~$ ros2 service call /turtle1/teleport_
turtlesim/srv/TeleportRelative "{linear: 0.0, angular: 1.57079632679}"
waiting for service to become available...
requester: making request: turtlesim.srv.TeleportRelative_Request(linea
gular=1.57079632679)

response:
turtlesim.srv.TeleportRelative_Response()

yahboom@yahboom-virtual-machine:~$ ros2 service call /turtle1/teleport_
turtlesim/srv/TeleportRelative "{linear: 2.0, angular: 0.0}"
requester: making request: turtlesim.srv.TeleportRelative_Request(linea
gular=0.0)

response:
turtlesim.srv.TeleportRelative_Response()

yahboom@yahboom-virtual-machine:~$ ros2 service call /turtle1/teleport_
turtlesim/srv/TeleportRelative "{linear: 0.0, angular: 1.57079632679}"
waiting for service to become available...
requester: making request: turtlesim.srv.TeleportRelative_Request(linear=0.0, an
gular=1.57079632679)

response:
turtlesim.srv.TeleportRelative_Response()

yahboom@yahboom-virtual-machine:~$ ros2 service call /turtle1/teleport_relative
turtlesim/srv/TeleportRelative "{linear: 2.0, angular: 0.0}"
waiting for service to become available...
```



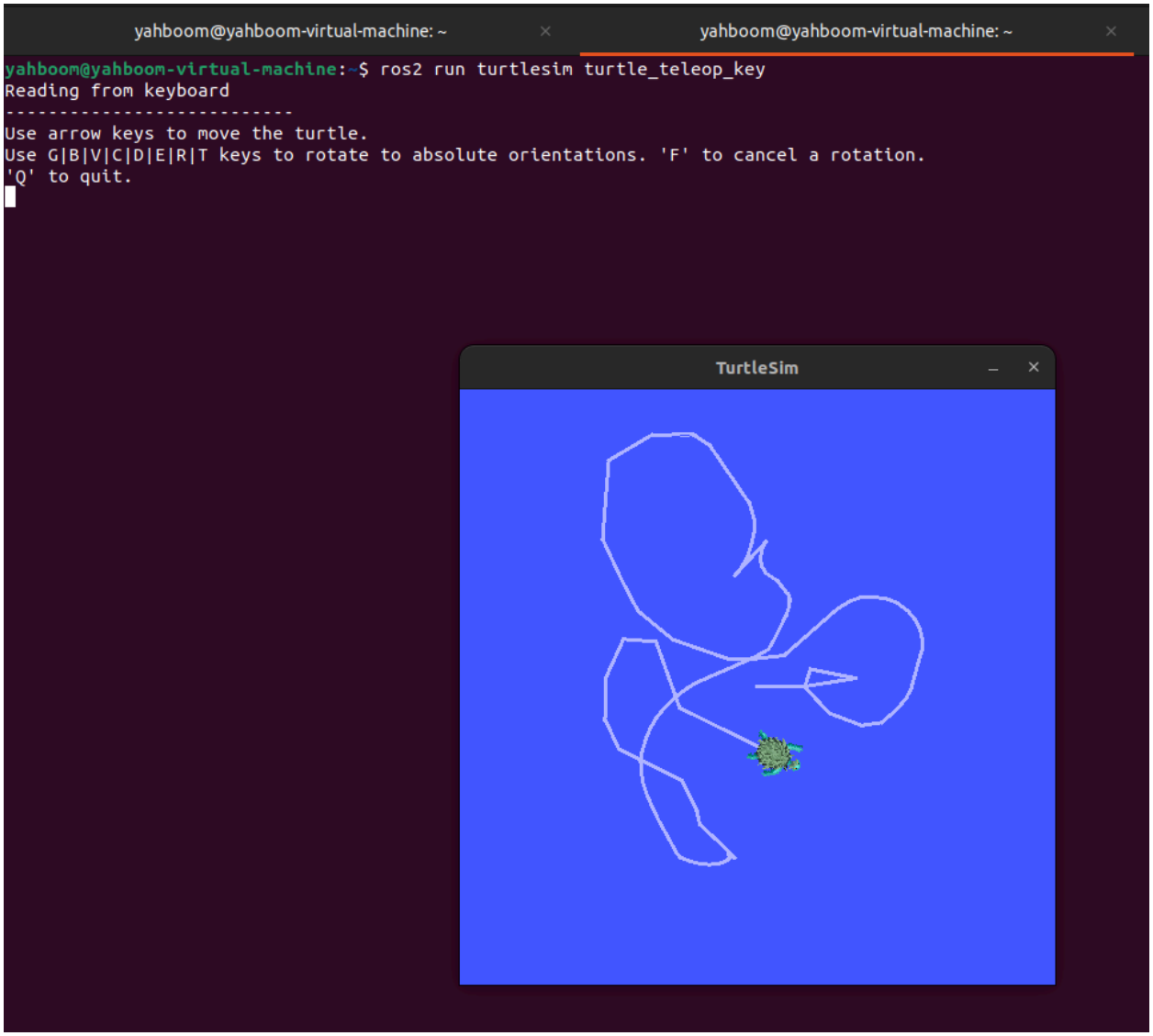
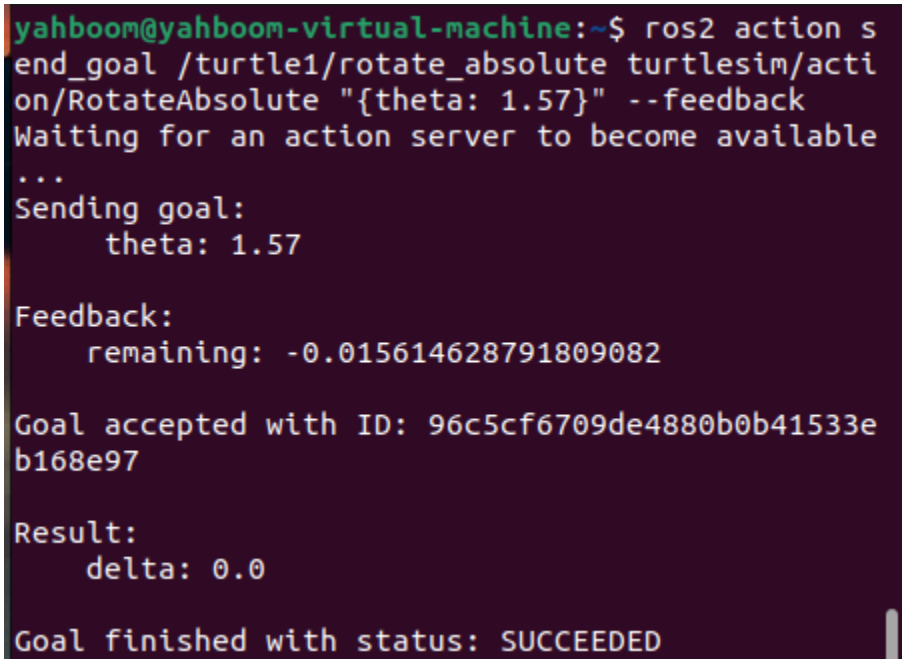
Here are the commands and output using the provided command.



Here is the output of the line being changed to red.



Here is a screenshot of the turtle_teleop working.



Here is the feedback on the position/status of the turtle.