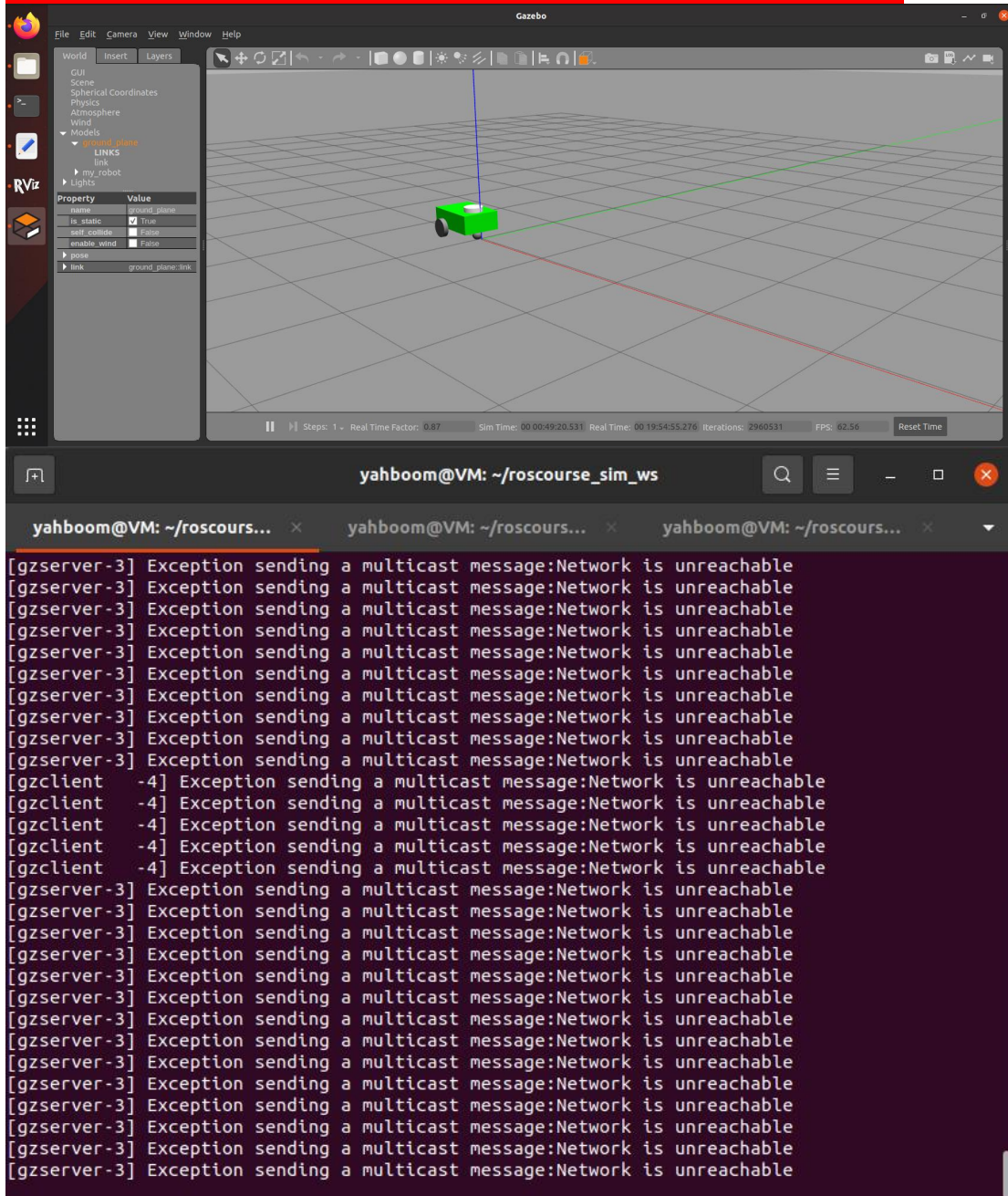


Deliverables added after debugging for task 4



```
yahboom@VM: ~  
-----  
ROS VERSION: ros-foxy | ROS_DOMAIN_ID: 66  
-----  
yahboom@VM:~$ ros2 topic list -t  
/clicked_point [geometry_msgs/msg/PointStamped]  
/clock [roscpp_msgs/msg/Clock]  
/cmd_vel [geometry_msgs/msg/Twist]  
/goal_pose [geometry_msgs/msg/PoseStamped]  
/initialpose [geometry_msgs/msg/PoseWithCovarianceStamped]  
/joint_states [sensor_msgs/msg/JointState]  
/odom [nav_msgs/msg/Odometry]  
/parameter_events [rcl_interfaces/msg/ParameterEvent]  
/performance_metrics [gazebo_msgs/msg/PerformanceMetrics]  
/robot_description [std_msgs/msg/String]  
/rosout [rcl_interfaces/msg/Log]  
/tf [tf2_msgs/msg/TFMessage]  
/tf_static [tf2_msgs/msg/TFMessage]  
yahboom@VM:~$  
  
y=0.0, z=0.0), angular=geometry_msgs.msg.Vector3(x=0.0, y=0.0, z=0.0))  
  
publishing #17: geometry_msgs.msg.Twist(linear=geometry_msgs.msg.Vector3(x=0.5,  
y=0.0, z=0.0), angular=geometry_msgs.msg.Vector3(x=0.0, y=0.0, z=0.0))  
  
publishing #18: geometry_msgs.msg.Twist(linear=geometry_msgs.msg.Vector3(x=0.5,  
y=0.0, z=0.0), angular=geometry_msgs.msg.Vector3(x=0.0, y=0.0, z=0.0))  
  
publishing #19: geometry_msgs.msg.Twist(linear=geometry_msgs.msg.Vector3(x=0.5,  
y=0.0, z=0.0), angular=geometry_msgs.msg.Vector3(x=0.0, y=0.0, z=0.0))  
  
publishing #20: geometry_msgs.msg.Twist(linear=geometry_msgs.msg.Vector3(x=0.5,  
y=0.0, z=0.0), angular=geometry_msgs.msg.Vector3(x=0.0, y=0.0, z=0.0))  
  
publishing #21: geometry_msgs.msg.Twist(linear=geometry_msgs.msg.Vector3(x=0.5,  
y=0.0, z=0.0), angular=geometry_msgs.msg.Vector3(x=0.0, y=0.0, z=0.0))  
  
publishing #22: geometry_msgs.msg.Twist(linear=geometry_msgs.msg.Vector3(x=0.5,  
y=0.0, z=0.0), angular=geometry_msgs.msg.Vector3(x=0.0, y=0.0, z=0.0))  
  
publishing #23: geometry_msgs.msg.Twist(linear=geometry_msgs.msg.Vector3(x=0.5,  
y=0.0, z=0.0), angular=geometry_msgs.msg.Vector3(x=0.0, y=0.0, z=0.0))  
  
|
```

