

Lab 3 Proof of Completion

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Task 2

The image displays three terminal windows side-by-side, each showing the output of a ROS command. The first window shows the definition of the `turtle_pose` message, which includes a `Point position` and a `Quaternion orientation`. The second window shows the definition of the `SetPose` service, which includes a `Header header`, a `Time stamp`, a `string frame_id`, and a `Pose pose` (which contains a `Point position` and a `Quaternion orientation`). The third window shows the definition of the `SetColor` service, which includes a `string color`.

```
yahboom@yahboom-virtual-machine:~$ source ~/roscourse_ws/install/setup.bash
yahboom@yahboom-virtual-machine:~$ ros2 interface show turtle_interfaces/msg/TurtleMsg
string name
geometry_msgs/Pose turtle_pose
    Point position
        float64 x
        float64 y
        float64 z
    Quaternion orientation
        float64 x 0
        float64 y 0
        float64 z 0
        float64 w 1
string color
yahboom@yahboom-virtual-machine:~$ 
```

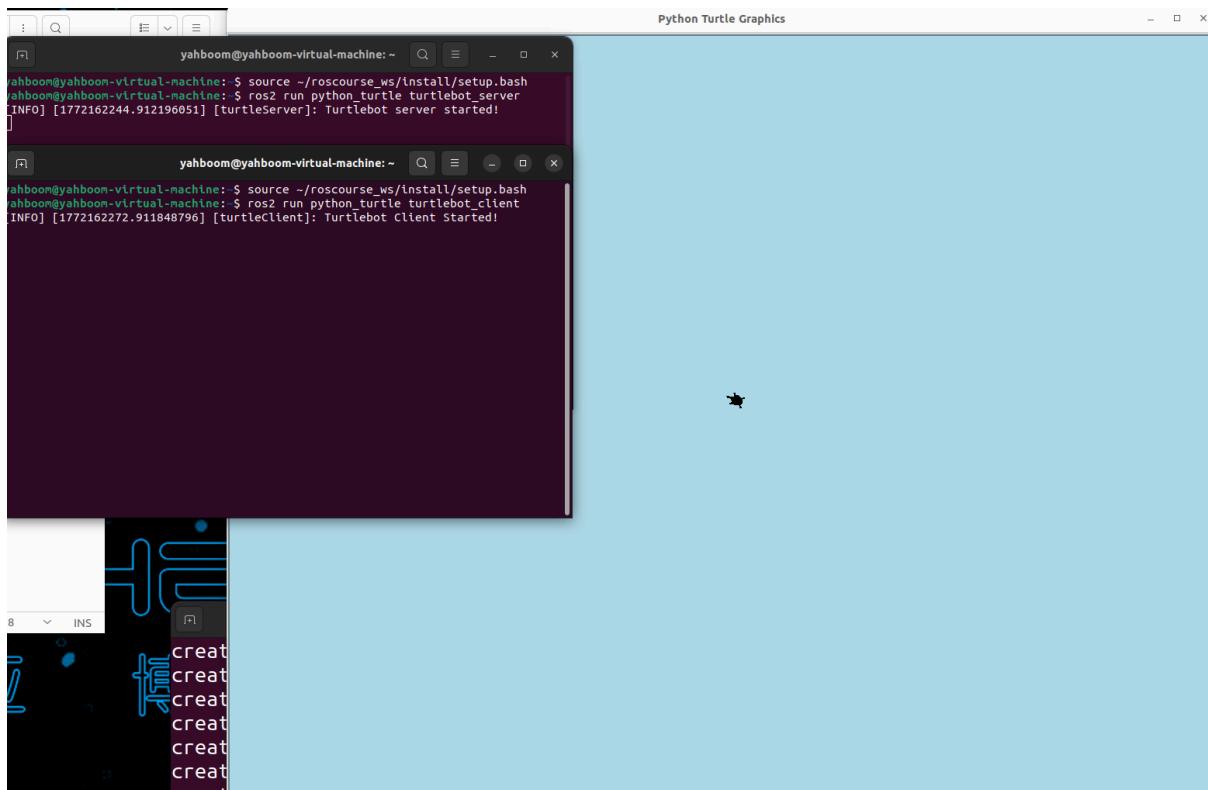


```
yahboom@yahboom-virtual-machine:~$ source ~/roscourse_ws/install/setup.bash
yahboom@yahboom-virtual-machine:~$ ros2 interface show turtle_interfaces/srv/SetPose
geometry_msgs/PoseStamped turtle_pose
    std_msgs/Header header
        builtin_interfaces/Time stamp
            int32 sec
            uint32 nanosec
        string frame_id
    Pose pose
        Point position
            float64 x
            float64 y
            float64 z
        Quaternion orientation
            float64 x 0
            float64 y 0
            float64 z 0
            float64 w 1
...
int8 ret
yahboom@yahboom-virtual-machine:~$ 
```



```
yahboom@yahboom-virtual-machine:~$ source ~/roscourse_ws/install/setup.bash
yahboom@yahboom-virtual-machine:~$ ros2 interface show turtle_interfaces/srv/SetColor
string color
...
int8 ret
yahboom@yahboom-virtual-machine:~$ 
```

Task 3



Task 4

