

# Activity 1 - interacting with the Turtlesim

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to set your own TURTLE\_NAME use the following command. Otherwise you have been given a unique TURTLE\_NAME co-responding to your container

```
export TURTLE_NAME=3
```

For the purpose of this

Show all services

```
ros2 service list
```

Step X: get the type of message used by the spawn service

```
ros2 service type /spawn
```

additionally you could list all types

```
ros2 service list -t
```

Step X: get the interface of /spawn

```
ros2 interface show <enter_spawn_type_from_step_X>
```

You should see something of the following form:

```
float32 x
float32 y
float32 theta
string name # Optional. A unique name will be created and returned if this is
empty
---
string name
```

Step X: call the spawn service in YAML syntax

```
ros2 service call /spawn turtlesim/srv/Spawn "{x: 2, y: 2, theta: 0.2, name: '$TURTLE_NAME'}"
```

Step X: start a teleop process

```
ros2 run turtlesim turtle_teleop_key --ros-args --remap  
turtle1/cmd_vel:=$TURTLE_NAME/cmd_vel
```

Follow the prompts in your terminal to control your turtle up on the screen.

## Additional steps

Step X: teleport your turtle