



speed\_X=[-100, 100], positive number is forward turn, negative number is backward turn.

Return value: none.

## **7.3. Experimental results**

Refer to 4.3.1, 4.3.2 to check the ROS expansion board as well as enter the Docker container, and then run the program, in the jupyter lab interface, double-click to enter the /root/yahboomcar\_ros2\_ws/Rosmaster/Sample, double-click to select the 5.pwm\_servo.ipynb, and then step-by-step click on the 4.3. 3 The button shown in the figure operates the program.

## **7.4 Program Source Code**

Enter the docker, refer to the code path:

/root/yahboomcar\_ros2\_ws/Rosmaster/Sample/7.motor.ipynb