#!/usr/bin/env python3

import rclpy

from rclpy.node import Node

from std\_msgs.msg import Int32

import math

import time

class three\_node(Node):

def \_\_init\_\_(self):

super().\_\_init\_\_("Three\_node")

self.get\_logger().info("Node has been started....")

self.counter = 0

# self.timer\_ = self.create\_timer(1.0,self.timer\_callback)## This is timer for publishing.....Hello String....

self.subscribe\_=self.create\_subscription(Int32, "/msg\_count",self.subscriber\_callback,10) ### Created subscriber that subscribes to same topic..

## called /message topic

def subscriber\_callback(self,msg\_a):## Subscribed callback function....where Hello String is available....

self.get\_logger().info(str(msg\_a.data))

def main(args=None):

rclpy.init(args=args)

node = three\_node()

rclpy.spin(node)

rclpy.shutdown()

if \_\_name\_\_=="\_\_main\_\_":

main()