#!/usr/bin/env python3

import rclpy

from rclpy.node import Node

from turtlesim.msg import Pose

from geometry\_msgs.msg import Twist

import math

# from turtle\_control import TurtleControllerNode

class traingle(Node):

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

super().\_\_init\_\_("turtle\_controller")

self.length\_y = 3.0

self.theta = math.pi

self.pose\_ = None

self.cmd\_vel\_publisher\_ = self.create\_publisher(Twist, "turtle1/cmd\_vel", 10)

self.pose\_subscriber\_ = self.create\_subscription(Pose, "turtle1/pose", self.callback\_turtle\_pose, 10)

self.control\_loop\_timer\_ = self.create\_timer(0.01, self.control\_loop)

def callback\_turtle\_pose(self,msg):

self.pose\_ = msg

def control\_loop(self):

if self.pose\_ == None:

return

msg = Twist()

msg.linear.x = self.length\_y

msg.angular.z = self.theta

self.cmd\_vel\_publisher\_.publish(msg)

def main(args=None):

rclpy.init(args=args)

tri = traingle()

rclpy.spin(tri)

rclpy.shutdown()

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

main()