```python
#!/usr/bin/env python

from __future__ import print_function

import roslib; roslib.load_manifest('teleop_twist_keyboard')
import rospy

from geometry_msgs.msg import Twist
from std_msgs.msg import Empty

import sys, select, termios, tty

msg = """
Reading from the keyboard  and Publishing to Twist!
---------------------------
Moving around:
   u    i    o
   j    k    l
   m    ,    .

For Holonomic mode (strafing), hold down the shift key:
---------------------------
   U    I    O
```

```
   J    K    L
   M    <    >

t : up (+z)
b : down (-z)

anything else : stop

q/z : increase/decrease max speeds by 10%
w/x : increase/decrease only linear speed by 10%
e/c : increase/decrease only angular speed by 10%

CTRL-C to quit
"""


moveBindings = {
        'i':(1,0,0,0),
        'o':(1,0,0,-1),
        'j':(0,0,0,1),
        'l':(0,0,0,-1),
        'u':(1,0,0,1),
        ',':(-1,0,0,0),
        '.':(-1,0,0,1),
```

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    'm':(-1,0,0,-1),
    'O':(1,-1,0,0),
    'I':(1,0,0,0),
    'J':(0,1,0,0),
    'L':(0,-1,0,0),
    'U':(1,1,0,0),
    '<':(-1,0,0,0),
    '>':(-1,-1,0,0),
    'M':(-1,1,0,0),
    't':(0,0,1,0),
    'b':(0,0,-1,0),
    }

speedBindings={
    'q':(1.1,1.1),
    'z':(.9,.9),
    'w':(1.1,1),
    'x':(.9,1),
    'e':(1,1.1),
    'c':(1,.9),
    }

flying_mode = False
```

```python
def getKey():
    tty.setraw(sys.stdin.fileno())
    select.select([sys.stdin], [], [], 0)
    key = sys.stdin.read(1)
    termios.tcsetattr(sys.stdin, termios.TCSADRAIN, settings)
    return key


def vels(speed,turn):
    return "currently:\tspeed %s\tturn %s " % (speed,turn)

if __name__=="__main__":
    settings = termios.tcgetattr(sys.stdin)

    pub = rospy.Publisher('/bebop/cmd_vel', Twist, queue_size = 1)
    pubTakeoff = rospy.Publisher('/bebop/takeoff', Empty, queue_size=10)
    pubLand = rospy.Publisher('/bebop/land', Empty, queue_size=10)

    rospy.init_node('teleop_twist_keyboard')

    speed = rospy.get_param("~speed", 0.5)
    turn = rospy.get_param("~turn", 1.0)
```

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x = 0
y = 0
z = 0
th = 0
status = 0

try:
    print(msg)
    print(vels(speed,turn))
    while(1):
        key = getKey()
        if key == ' ':
            if flying_mode:
                flying_mode = False
                pubLand.publish(Empty())
            else:
                flying_mode = True
                pubTakeoff.publish(Empty())
        elif key in moveBindings.keys():
            x = moveBindings[key][0]
            y = moveBindings[key][1]
            z = moveBindings[key][2]
            th = moveBindings[key][3]
```

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        elif key in speedBindings.keys():
            speed = speed * speedBindings[key][0]
            turn = turn * speedBindings[key][1]

            print(vels(speed,turn))
            if (status == 14):
                print(msg)
            status = (status + 1) % 15
        else:
            x = 0
            y = 0
            z = 0
            th = 0
            if (key == '\x03'):
                break

        twist = Twist()
        twist.linear.x = x*speed; twist.linear.y = y*speed; twist.linear.z = z*speed;
        twist.angular.x = 0; twist.angular.y = 0; twist.angular.z = th*turn
        pub.publish(twist)

except Exception as e:
    print(e)
```

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finally:
    twist = Twist()
    twist.linear.x = 0; twist.linear.y = 0; twist.linear.z = 0
    twist.angular.x = 0; twist.angular.y = 0; twist.angular.z = 0
    pub.publish(twist)

    termios.tcsetattr(sys.stdin, termios.TCSADRAIN, settings)
```