```
%To initialize run the following line to set up ros's connection to matlab
% rosinit('10.0.75.2',11311,'NodeHost','10.0.75.1')
%--------------------------------------------------------------------------%
pub = rospublisher('/raw_vel');          %set up publisher for velocity to be written
to later
msg = rosmessage(pub);                   %establishes message object containing
publisher
d = 0.24765;                             %distance between wheels in meters
w = pi/5;                                %angular velocities
v = d*w;                                 %linear velocity
vR = w*((v/w)+(d/2));                    %right wheel velocity
vL = w*((v/w)-(d/2));                    %left wheel velocity
endTime = 2*pi/w;                        %time it theoretically takes to complete one
circle
msg.Data = [vL, vR];                     %writes velocities to message data object
send(pub, msg);                          %sends velocities to wheels
tStart = tic();                          %establishes start time of while loop
elapsed = 0;                             %establish elapsed
while elapsed <= endTime
    elapsed = toc(tStart);               %check to determine whether to stop neto
end
msg.Data = [0,0];                        %writes zero velocities to data message
object neto
send(pub, msg);                          %sends zero velocities to robot
%rosshutdown
```