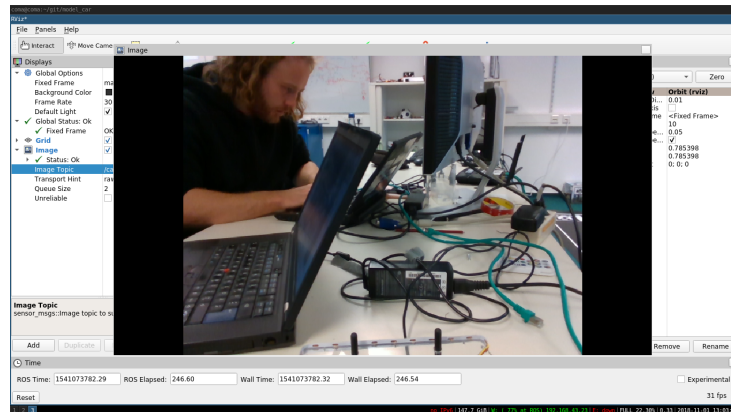


## 1 Aufgabe 1



## 2 Aufgabe 2

```
data: "I heard: -0.148836001754"
data: "I heard: -0.149436056614"
data: "I heard: -0.149948328733"
data: "I heard: -0.149829342961"
data: "I heard: -0.149199575186"
data: "I heard: -0.148600012064"
data: "I heard: -0.14835575223"
data: "I heard: -0.148594677448"
data: "I heard: -0.149197220802"
data: "I heard: -0.149677798152"
data: "I heard: -0.149950265884"
data: "I heard: -0.149561703205"
data: "I heard: -0.148839324713"
data: "I heard: -0.148477122188"
data: "I heard: -0.148354783654"
data: "I heard: -0.148836001754"
data: "I heard: -0.149437010288"
data: "I heard: -0.149949297309"
data: "I heard: -0.149831831455"
data: "I heard: -0.149200543761"
data: "I heard: -0.148600965738"
data: "I heard: -0.148357227445"
data: "I heard: -0.148596137762"
data: "I heard: -0.149075865746"
data: "I heard: -0.149676829576"
data: "I heard: -0.149949297309"
data: "I heard: -0.149562239647"
data: "I heard: -0.148959726095"
data: "I heard: -0.148478612304"
data: "I heard: -0.14835382998"
data: "I heard: -0.148836001754"
data: "I heard: -0.149314209819"
data: "I heard: -0.149825468659"
I
steved::kivi kivi ::Local: 192.168.43.24 Public: 160.45.112.201 1:editor*Z 2 nvim- 01/11 13:10:53
```

Den Quellcode finden sie hier [https://github.com/bigzed/model\\_car/blob/version-4.0/catkin\\_ws/src/assignment1\\_publisher\\_subscriber/src/publisher\\_subscriber.py](https://github.com/bigzed/model_car/blob/version-4.0/catkin_ws/src/assignment1_publisher_subscriber/src/publisher_subscriber.py) oder auf der nächsten Seite.

```
1 #!/usr/bin/env python
2 import rospy
3 from std_msgs.msg import String
4 from std_msgs.msg import Float32
5
6 def callback(data):
7     publisher.publish(String('I heard: {}'.format(data.data)))
8
9 def listener():
10     global publisher
11     # init node
12     rospy.init_node('assignment1_publisher_subscriber', anonymous=True)
13     # create publisher
14     publisher = rospy.Publisher('/assignment1_publisher_subscriber', String,
15     → queue_size = 10)
16     # subscribe with callback
17     rospy.Subscriber('/yaw', Float32, callback)
18
19     rospy.spin()
20
21 if __name__ == '__main__':
22     listener()
```