AA274A Section 3

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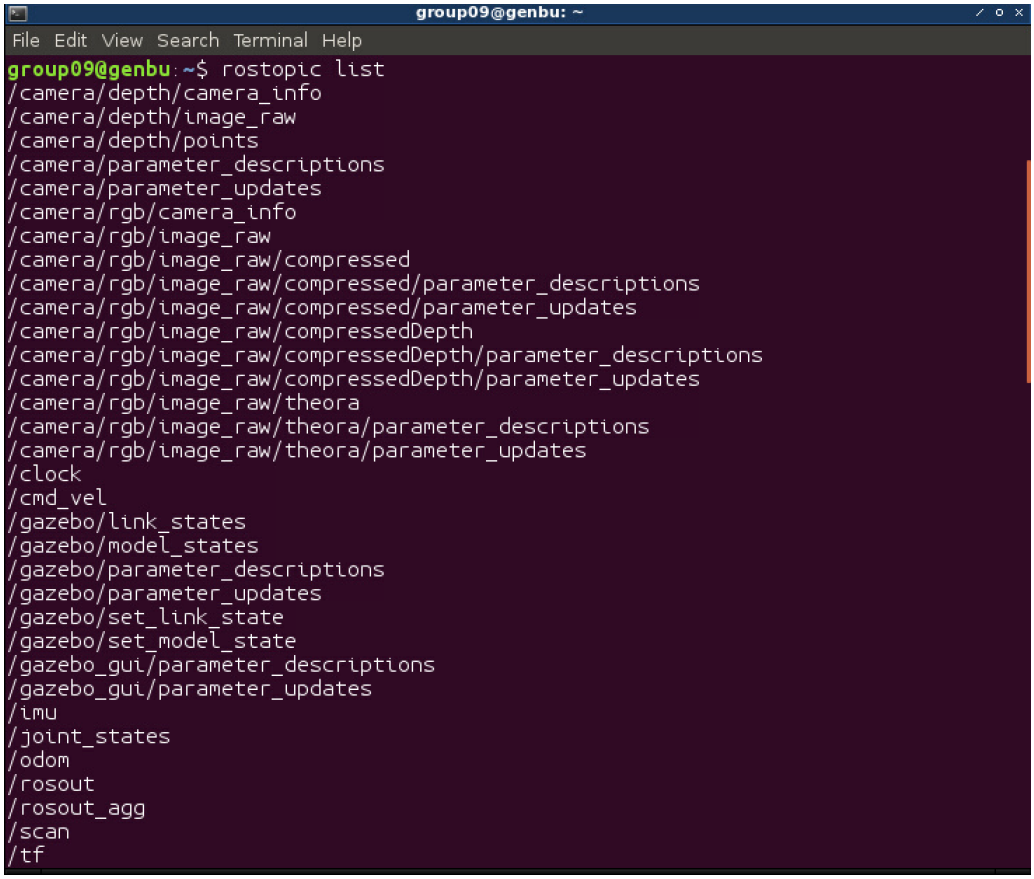
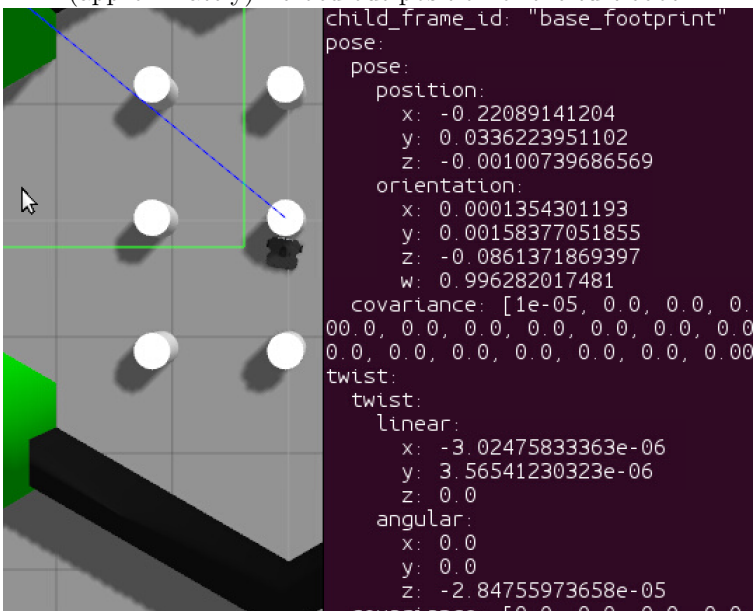
Problem 1

List of rostopics:



Problem 2

(approximately) Zeroed-out position of the turtlebot:

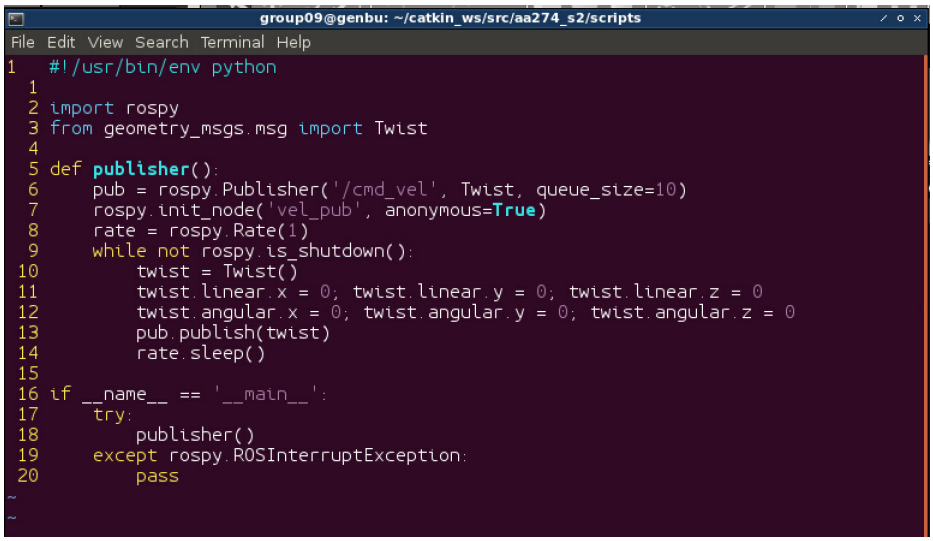


Message type: nav_msgs/Odometry

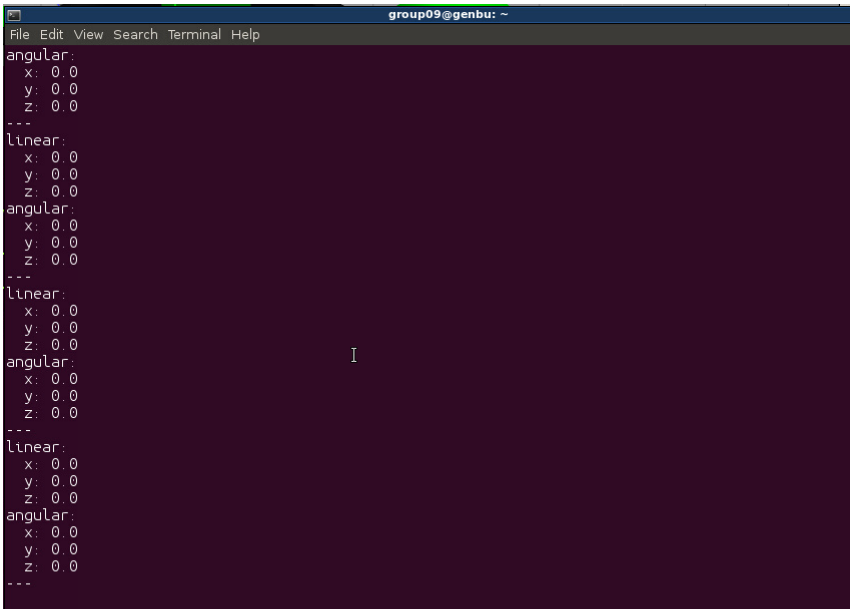
The message contains position (x,y,z), orientation (x,y,z,w), linear and angular velocity, and covariances

Problem 3

Python code for publisher:



Commanded linear and angular velocities:



Problem 4

Python code for subscriber:

group09@genbu: ~/catkin_ws/src/aa274_s2/scripts

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

import rospy
from nav_msgs.msg import Odometry

def callback(data):
    rospy.loginfo(rospy.get_caller_id() + str(data))

def subscriber():
    rospy.init_node('odom_sub', anonymous=True)
    rospy.Subscriber("/odom", Odometry, callback)
    rospy.spin()

if __name__ == '__main__':
    subscriber()
```

Odometry information read by subscriber: