

```

1 checkpoint2-1-go-forward.l
2
3 buffers
4
5
6
7 (turtlebot-init)
8
9 (ros::ros-info "start !!!")
10
11 (while t
12   (when (not (= (norm (send *ri* :state :button-vector)) 0))
13     (send *ri* :publish-sound 1)
14     (return-from nil nil))
15 )
16
17 (while t
18   (send *ri* :go-velocity 0.1 0 0)
19   (when (not (= (norm (send *ri* :state :bumper-vector)) 0)) ;; ひとつでも非ゼロなら
20     (send *ri* :go-velocity 0 0 0)
21     (return-from nil nil))
22 )
23
24 (exit)

```

NORMAL checkpoint2-1-go-forward.l lex utf-8 50% 12/24

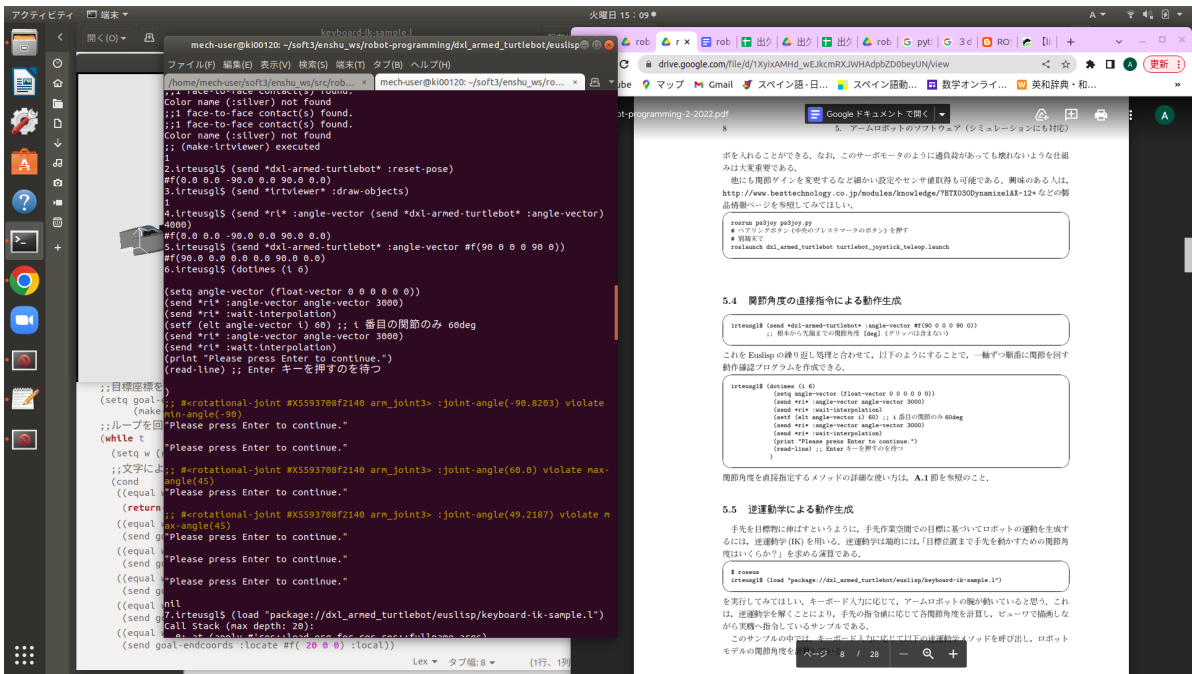
```

[ WARN] [1669093894.720821602]: #<controller-action-client #X56313ed34ea8 fullbody_controller/follow_joint_trajectory_action> is not respond, turtlebot-interface is disabled
[ WARN] [1669093894.720840471]: Starting 'Kinematics Simulator'
[ WARN] [1669093894.720864095]: (If you do not intend to start Kinematics Simulator, make sure that you can run 'rostopic info /fullbody_controller/follow_joint_trajectory_action/goal' and 'rostopic info /fullbody_controller/follow_joint_trajectory_action/cancel' and check whether Subscribers exists. If there is no Subscribers, please check joint_trajectory_action node.)
[ WARN] [1669093894.720883334]: (Please also check 'rostopic info /fullbody_controller/follow_joint_trajectory_action/feedback' and 'rostopic info /fullbody_controller/follow_joint_trajectory_action/result' and check whether Publishers exists. If there is no Publishers, please check joint_trajectory_action node.)
[ WARN] [1669093894.720906604]: (If joint_trajectory_action node already exists, you might have a network problem. Please make sure that you can run 'rostopic ping JOINT_TRAJECTORY_ACTION_SERVER_NODE_NAME' and 'rostopic ping /checkpoint2_1_go_forward_1669093891522418221')
;; (make-irtviewer) executed
[ INFO] [1669093894.867830946]: start !!!
[ INFO] [1669093915.795067198]: cell* ROSEUS_EXIT(context*, int, cell**)
[ INFO] [1669093915.795100636]: exiting roseus 0

```

[illegible]

## checkpoint 2- 2



## checkpoint 2- 3

