

# Point::Pub:State::Static:::

Topic	Node	Comments	Result
/mobile_base/debug/raw_data_command::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [22 ]	~
/gateway/force_update::	/app_manager	* Stopped publishing on the topic by commenting [1 ]	~
/cmd_vel_mux/parameter_descriptions::	/mobile_base_nodelet_manager	**	
/mobile_base/events/robot_state::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [2 ]	X
/mobile_base/debug/raw_data_stream::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [3 ]	
/odom::	/mobile_base_nodelet_manager	***	
/mobile_base/sensors/core::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [4 ] * After modifying the file the topic was still present ~ /mobile_base_nodelet_manager is still subscribing to it	!
/cmd_vel_mux/parameter_updates::	/mobile_base_nodelet_manager	****	
/mobile_base/events/button::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [5 ]	!
/mobile_base/sensors/bumper::	/mobile_base_nodelet_manager	*****	
/interactions/pairing::	/interactions	* Treated as a generalization, I killed /iterations node and the system didn't break	~
/turtlebot/incompatible_rapp_list::	/app_manager	* Stopped publishing on the topic by commenting [7 ]	X
/capability_server/bonds::	/capability_server /app_manager	*****	
/tf_static::	/robot_state_publisher	* Treated as a generalization, I killed /iterations node and the system didn't break	~
/mobile_base/events/power_system::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [8 ]	X
/cmd_vel_mux/active::	/mobile_base_nodelet_manager	*****	
/diagnostics::	/mobile_base_nodelet_manager	*****	
/mobile_base/events/digital_input::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [9 ]	X
/mobile_base/debug/raw_control_command::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [10 ]	~
/zeroconf/new_connections::	/zeroconf/zeroconf	*****	
/mobile_base/events/wheel_drop::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [11 ]	!
/interactions/interactive_clients::	/interactions	<a href="http://wiki.ros.org/rocon_interactions">http://wiki.ros.org/rocon_interactions</a>	
/info::	/master	*****	

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/joint_states::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [ 12 ]	X
/mobile_base/sensors/imu_data_raw::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [ 13 ]	X
/mobile_base/sensors/dock_ir::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [ 14 ]	~
/mobile_base/events/bumper::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [ 6 ]	!
/turtlebot/status::	/app_manager	* Stopped publishing on the topic by commenting [ 20 ] * minimal keeps showing errors but the system doesn't actually crash. Teleop still controls the turtlebot. * It also removes all the /turtlebot topics	!
/mobile_base/commands/velocity::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [ 15 ] * The turtlebot doesn't move	@
/diagnostics_toplevel_state::	/diagnostic_aggregator	* Treated as a generalization, I killed /diagnostic_aggregator node and the system didn't break	X
/mobile_base/controller_info::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [ 16 ]	~
/turtlebot/rapp_list::	/app_manager	* Stopped publishing on the topic by commenting [ 21 ]	!
/mobile_base/events/cliff::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [ 17 ]	!
/mobile_base/sensors/imu_data::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [ 18 ]	~
/zeroconf/lost_connections::	/zeroconf/zeroconf	* Treated as a generalization, I killed /zeroconf/zeroconf node and the system didn't break	X
/mobile_base/version_info::	/mobile_base_nodelet_manager	* Stopped publishing on the topic by commenting [ 19 ]	X
/cmd_vel_mux/input/teleop::	/turtlebot_teleop_keyboard	**Not applicable**	
/diagnostics_agg::	/diagnostic_aggregator	* Treated as a generalization, I killed /diagnostic_aggregator node and the system didn't break * <a href="http://docs.ros.org/kinetic/api/diagnostic_aggregator/html/">http://docs.ros.org/kinetic/api/diagnostic_aggregator/html/</a>	X
/capability_server/events::	/capability_server	**Not applicable**	

Program Point: /rec/arch\_pub

!: Crashes when activated;

~: Doesn't seem to crash;

X: Crashes start

@: Malfunctions

x: 10    !: 7    ~: 8    @: 1

Total: 26

## Point::Pub:State::Static:::

#	Description
1	<pre>point::pub:state::static:topic::gateway/force_update:node::app_manager:: File::~~lib/python2.7/dist-packages/rocon_app_manager/rapp_manager.py Line::139:142:: self._gateway_publishers['force_update'] = rospy.Publisher("~/force_update", std_msgs.Empty, queue_size=5)</pre>
2	<pre>point::pub:state::static:topic::mobile_base/events/robot_state:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::321:: robot_event_publisher = nh.advertise &lt; kobuki_msgs::RobotStateEvent &gt; ("events/robot_state", 100, true);</pre>
3	<pre>point::pub:state::static:topic::mobile_base/debug/raw_data_stream:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::327:: raw_data_stream_publisher = nh.advertise &lt; kobuki_msgs::String &gt; ("debug/raw_data_stream", 100);</pre>
4	<pre>point::pub:state::static:topic::mobile_base/sensors/core:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::322:: sensor_state_publisher = nh.advertise &lt; kobuki_msgs::SensorState &gt; ("sensors/core", 100);</pre>
5	<pre>point::pub:state::static:topic::mobile_base/events/button:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::315:: button_event_publisher = nh.advertise &lt; kobuki_msgs::ButtonEvent &gt; ("events/button", 100);</pre>
6	<pre>point::pub:state::static:topic::mobile_base/sensors/bumper:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::mobile_base_nodelet_manager:: bumper_event_publisher = nh.advertise &lt; kobuki_msgs::BumperEvent &gt; ("events/bumper", 100);</pre>
7	<pre>point::pub:state::static:topic::turtlebot/incompatible_rapp_lis:node::app_manager File::~~lib/python2.7/dist-packages/rocon_app_manager/rapp_manager.py Line::188:: self._publishers['incompatible_rapp_list'] = rospy.Publisher(self._publisher_names['incompatible_rapp_list'], rapp_manager_msgs.IncompatibleRappList, latch=True, queue_size=1)</pre>
8	<pre>point::pub:state::static:topic::mobile_base/events/power_system:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::319:: power_event_publisher = nh.advertise &lt; kobuki_msgs::RobotStateEvent &gt; ("events/power_system", 100);</pre>
9	<pre>point::pub:state::static:topic::mobile_base/events/digital_input:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::320:: input_event_publisher = nh.advertise &lt; kobuki_msgs::DigitalInputEvent &gt; ("events/digital_input", 100);</pre>
10	<pre>point::pub:state::static:topic::mobile_base/debug/raw_control_command:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::328:: raw_control_command_publisher = nh.advertise&lt; std_msgs::Int16MultiArray &gt; ("debug/raw_control_command", 100)</pre>
11	<pre>point::pub:state::static:topic::mobile_base/events/wheel_drop:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::318:: wheel_event_publisher = nh.advertise &lt; kobuki_msgs::WheelDropEvent &gt; ("events/wheel_drop", 100);</pre>
12	<pre>point::pub:state::static:topic::joint_states:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp Line::308 :: joint_state_publisher = nh.advertise &lt;sensor_msgs::JointState&gt;("joint_states",100);</pre>
13	<pre>point::pub:state::static:topic::mobile_base/sensors/imu_data_raw:node::mobile_base_nodelet_manager:: File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp</pre>

## Point::Pub:State::Static:::

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Line::325 :::
raw_imu_data_publisher = nh.advertise < sensor_msgs::Imu > ("sensors/imu_data_raw", 100);
14 point::pub:state::static:topic::/mobile_base/sensors/dock_ir::/mobile_base_nodelet_manager::
   File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp
   Line::323 :::
   dock_ir_publisher = nh.advertise < kobuki_msgs::DockInfraRed > ("sensors/dock_ir", 100);
15 point::pub:state::static:topic::/mobile_base/commands/velocity::/mobile_base_nodelet_manager::
   File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp
   Line::337 :::
   velocity_command_subscriber = nh.subscribe(std::string("commands/velocity"), 10,
&KobukiRos::subscribeVelocityCommand, this);
16 point::pub:state::static:topic::/mobile_base/controller_info::/mobile_base_nodelet_manager::
   File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp
   Line::345:::
   controller_info_command_subscriber = nh.subscribe(std::string("commands/controller_info"), 10,
&KobukiRos::subscribeControllerInfoCommand, this);
17 point::pub:state::static:topic::/mobile_base/events/cliff::/mobile_base_nodelet_manager::
   File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp
   Line::317:::
   cliff_event_publisher = nh.advertise < kobuki_msgs::CliffEvent > ("events/cliff", 100);
18 point::pub:state::static:topic::/mobile_base/sensors/imu_data::/mobile_base_nodelet_manager::
   File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp
   Line::324:::
   imu_data_publisher = nh.advertise < sensor_msgs::Imu > ("sensors/imu_data", 100);
19
   File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp
   Line::313:::
   version_info_publisher = nh.advertise < kobuki_msgs::VersionInfo > ("version_info", 100, true);
20 point::pub:state::static:topic::/turtlebot/status:node::/app_manager::
   File::~lib/python2.7/dist-packages/rocon_app_manager/rapp_manager.py
   Line::186:::
   self._publishers['status'] = rospy.Publisher(self._publisher_names['status'], rapp_manager_msgs.Status, latch=True,
queue_size=5)
21 point::pub:state::static:topic::/turtlebot/rapp_list:node::/app_manager::
   File::~lib/python2.7/dist-packages/rocon_app_manager/rapp_manager.py
   Line::187:::
   self._publishers['rapp_list'] = rospy.Publisher(self._publisher_names['rapp_list'], rapp_manager_msgs.RappList,
latch=True, queue_size=1)
22 point::pub:state::static:topic::/debug/raw_data_command::/mobile_base_nodelet_manager::
   File::rocon_kobuki_turtlebot/src/kobuki/kobuki_node/src/library/kobuki_ros.cpp
   Line::326:::
   raw_data_command_publisher = nh.advertise< std_msgs::String > ("debug/raw_data_command", 100);
```