|  |  |  |  |
| --- | --- | --- | --- |
| 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 | http://wiki.ros.org/rocon\_interactions |  |
| /info:: | /master | \*\*\*\*\*\*\*\*\*\*\* |  |
| /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  \*http://docs.ros.org/kinetic/api/diagnostic\_aggregator/html/ | 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

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| --- | --- |
| # | Description |
| 1 | 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)* |
| 2 | 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 < kobuki\_msgs::RobotStateEvent > (“events/robot\_state”, 100, true);* |
| 3 | 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 < kobuki\_msgs::String > (“debug/raw\_data\_stream”, 100);* |
| 4 | 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 < kobuki\_msgs::SensorState > (“sensors/core”, 100);* |
| 5 | 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 < kobuki\_msgs::ButtonEvent > (“events/button”, 100);* |
| 6 | 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 < kobuki\_msgs::BumperEvent > (“events/bumper”, 100);* |
| 7 | 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)* |
| 8 | 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 < kobuki\_msgs::RobotStateEvent > (“events/power\_system”, 100);* |
| 9 | 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 < kobuki\_msgs::DigitalInputEvent > ("events/digital\_input", 100);* |
| 10 | point::pub:state::static:topic::/mobile\_base/debug/raw\_control\_command::/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< std\_msgs::Int16MultiArray > ("debug/raw\_control\_command", 100)* |
| 11 | point::pub:state::static:topic::/mobile\_base/events/wheel\_drop::/mobile\_base\_nodelet\_manager:::  File::rocon\_kobuki\_turtlebot/src/kobuki/kobuki\_node/src/library/kobuki\_ros.cpp  Line::318:::  *wheel\_event\_publisher = nh.advertise < kobuki\_msgs::WheelDropEvent > ("events/wheel\_drop", 100);* |
| 12 | point::pub:state::static:topic::/joint\_states::/mobile\_base\_nodelet\_manager:::  File::rocon\_kobuki\_turtlebot/src/kobuki/kobuki\_node/src/library/kobuki\_ros.cpp  Line::308 :::  *joint\_state\_publisher = nh.advertise <sensor\_msgs::JointState>("joint\_states",100);* |
| 13 | point::pub:state::static:topic::/mobile\_base/sensors/imu\_data\_raw::/mobile\_base\_nodelet\_manager:::  File::rocon\_kobuki\_turtlebot/src/kobuki/kobuki\_node/src/library/kobuki\_ros.cpp  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);* |
|  |  |