```
/random_complex/init_state_y: 0.0
/random_complex/map/circle_num: 40
   /random_complex/map/obs_num: 300
   /random_complex/map/resolution: 0.1
   /random_complex/map/x_size: 20.0
   /random_complex/map/y_size: 20.0
/random_complex/map/z_size: 10.0
/random_complex/sensing/rate: 0.5
   /rosdistro: melodic
   /rosversion: 1.14.3
 * /waypoint_generator/waypoint_type: manual-lonely-way...
NODES
     demo_node (grid_path_searcher/demo_node)
     random_complex (grid_path_searcher/random_complex)
     waypoint_generator (waypoint_generator/waypoint_generator)
ROS_MASTER_URI=http://127.0.0.1:11311
process[demo_node-1]: started with pid [19811]
process[random_complex-2]: started with pid [19812]
process[waypoint_generator-3]: started with pid [19813]
Displays
   Fixed Frame
   Background Color
Frame Rate
Default Light
                       255; 255; 127
▼ ② Global Status: Warn
③ Fixed Frame
                       No tf data. Actual er...
→ ⇔ Grid
→ 人 Axes
  St. AllMan
 ClosedNodes
▶ ♥ closeNodesSequence

    OpenNodes
    gridPath
    ✓ Status: Ok

     Status: Ok
   Marker Topic
                       /demo_node/grid_p...
   Queue Size
Namespaces
                       100
 Marker
   Marker Topic
Queue Size
Namespaces
```

Zero

+

40,6156

Remove

Orbit (rviz) 0,01

<Fixed Frame>

1,42942 0,829797 -1.2685; 1.4731; 0.65286 Orbit (rviz)

Type: Orbit (rviz)

Reset

▼ Current View Near Clip Distance

Invert Z Axis Target Frame Distance

Distance 40,611
Focal Shape Size 0,05
Focal Shape Fixed Size 1/2
Yaw 1,4294
Pitch 0,8297
Focal Point -1,268
Orbit TappourpOtho Tappo