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Activities Terminal 13:41 28 يوليو
/home/hetaf/catkin_ws/src/arduino_robot_arm/robot_arm_pkg/launch/check_motors.launch http://localhost:11311
hetaf@hetaf-VirtualBox: ~
[ 0%] Built target trajectory_msgs_generate_messages_lisp
[ 0%] Built target object_recognition_msgs_generate_messages_eus
[ 0%] Built target object_recognition_msgs_generate_messages_nodejs
[ 0%] Built target octomap_msgs_generate_messages_nodejs
[ 0%] Built target octomap_msgs_generate_messages_py
[ 0%] Built target dynamic_reconfigure_generate_messages_lisp
[ 0%] Built target tf2_msgs_generate_messages_cpp
[ 0%] Built target sensor_msgs_generate_messages_py
[100%] Built target move_group_node
hetaf@hetaf-VirtualBox:~/catkin_ws$ roslaunch robot_arm_pkg check_motors.launch
... logging to /home/hetaf/.ros/log/3163a1be-4ccd-11ef-b9d9-51f558ffa743/roslaunch-hetaf-VirtualBox-19448.log
Checking log directory for disk usage. This may take a while.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://hetaf-VirtualBox:40603/

SUMMARY
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PARAMETERS
* /robot_description: <?xml version="1....
* /roscpp: noetic
* /rosversion: 1.16.0

NODES
/
  joint_state_publisher_gui (joint_state_publisher_gui/joint_state_publisher_gui)
  robot_state_publisher (robot_state_publisher/robot_state_publisher)
  rviz (rviz/rviz)

auto-starting new master
process[master]: started with pid [19456]
ROS_MASTER_URI=http://localhost:11311

setting /run_id to 3163a1be-4ccd-11ef-b9d9-51f558ffa743
process[rosout-1]: started with pid [19466]
started core service [/rosout]
process[robot_state_publisher-2]: started with pid [19473]
process[rviz-3]: started with pid [19474]
process[joint_state_publisher_gui-4]: started with pid [19475]
[ WARN] [1722162965.780423740]: The root link base has an inertia specified in the URDF, but KDL does not support a root link with an inertia. As a workaround, you can add an extra dummy link to your UR
DF.
[INFO] [1722162966.260843]: Centering
```



























