

Q: 终端报错部分有 ROS path [0] ... 部分？

```
root@ubuntu:/home/alan/Desktop/catkin_ws# cd src/nav_sim/launch
root@ubuntu:/home/alan/Desktop/catkin_ws/src/nav_sim/launch# roslaunch myrobot_w
rld.launch
... logging to /root/.ros/log/1766f276-394b-11e8-ad87-000c2947615d/roslaunch-ubu
ntu-5062.log
Checking log directory for disk usage. This may take awhile.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

[invalid <arg> tag: nav_sim
ROS path [0]=/opt/ros/kinetic/share/ros
ROS path [1]=/opt/ros/kinetic/share
arg xml is <arg name="world_name" value="$(find nav_sim)/urdf/wall.world"/>.
The traceback for the exception was written to the log file
```

A: ros 的工作空间 workspace 没有配置，或者配置了没有 source，请按照官网流程严格操作。

Q: cannot launch node of type [map_server/map_server]: map_server

```
process[robot_state_publisher-6]: started with pid [5179]
ERROR: cannot launch node of type [map_server/map_server]: map_server
ROS path [0]=/opt/ros/kinetic/share/ros
ROS path [1]=/home/alan/Desktop/catkin_ws/src
ROS path [2]=/opt/ros/kinetic/share
SpawnModel script started
[INFO] [1522985834.366661, 0.000000]: Loading model XML from ros parameter
[INFO] [1522985834.368595, 0.000000]: Waiting for service /gazebo/spawn_urdf_mod
el
```

A: sudo apt-get install ros-你的版本-map-server

如果缺失其他 package，比如 move-base 等等，
可以 sudo apt-get install ros-你的版本-move-base

Q: VTR_Panel 问题

```
[ERROR] [1522985835.198606134]: PluginLibFactory: The plugin for class 'vtr_rviz
plugin/VTRPanel' failed to load. Error: According to the loaded plugin descrip
tions the class vtr_rviz_plugin/VTRPanel with base class type rviz::Panel does n
ot exist. Declared types are rviz_plugin_tutorials/Teleop
```

A: 是因为我上传的 rviz 用到了我们实验室自己用的 plugin，是我操作失误了。

解决方案：

1. 删除 nav_sim/urdf/navigation.rviz 里面包含 VTR 的部分。利用 ctrl+f 查找。
2. 下载最新的配置文件：https://github.com/ZJUYH/nav_sim

有疑问请联系

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