/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp: In member function ‘bool GazeboRosTurtleBot3::init()’:

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:45:8: error: ‘robot\_model’ was not declared in this scope

 if (!robot\_model.compare("burger"))

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:47:5: error: ‘turning\_radius\_’ was not declared in this scope

 turning\_radius\_ = 0.08;

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:48:5: error: ‘rotate\_angle\_’ was not declared in this scope

 rotate\_angle\_ = 50.0 \* DEG2RAD;

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:49:5: error: ‘front\_distance\_limit\_’ was not declared in this scope

 front\_distance\_limit\_ = 0.7;

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:50:5: error: ‘side\_distance\_limit\_’ was not declared in this scope

 side\_distance\_limit\_ = 0.4;

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:54:5: error: ‘turning\_radius\_’ was not declared in this scope

 turning\_radius\_ = 0.1435;

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:55:5: error: ‘rotate\_angle\_’ was not declared in this scope

 rotate\_angle\_ = 40.0 \* DEG2RAD;

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:56:5: error: ‘front\_distance\_limit\_’ was not declared in this scope

 front\_distance\_limit\_ = 0.7;

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:57:5: error: ‘side\_distance\_limit\_’ was not declared in this scope

 side\_distance\_limit\_ = 0.6;

 ^

In file included from /opt/ros/kinetic/include/ros/ros.h:40:0,

 from /home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/include/turtlebot3\_gazebo/gazebo\_ros\_turtlebot3.h:22,

 from /home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:19:

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:59:32: error: ‘robot\_model’ was not declared in this scope

 ROS\_INFO("robot\_model : %s", robot\_model.c\_str());

 ^

/opt/ros/kinetic/include/ros/console.h:346:165: note: in definition of macro ‘ROSCONSOLE\_PRINT\_AT\_LOCATION\_WITH\_FILTER’

 ::ros::console::print(filter, \_\_rosconsole\_define\_location\_\_loc.logger\_, \_\_rosconsole\_define\_location\_\_loc.level\_, \_\_FILE\_\_, \_\_LINE\_\_, \_\_ROSCONSOLE\_FUNCTION\_\_, \_\_VA\_ARGS\_\_)

 ^

/opt/ros/kinetic/include/ros/console.h:379:7: note: in expansion of macro ‘ROSCONSOLE\_PRINT\_AT\_LOCATION’

 ROSCONSOLE\_PRINT\_AT\_LOCATION(\_\_VA\_ARGS\_\_); \

 ^

/opt/ros/kinetic/include/ros/console.h:561:35: note: in expansion of macro ‘ROS\_LOG\_COND’

 #define ROS\_LOG(level, name, ...) ROS\_LOG\_COND(true, level, name, \_\_VA\_ARGS\_\_)

 ^

/opt/ros/kinetic/include/rosconsole/macros\_generated.h:110:23: note: in expansion of macro ‘ROS\_LOG’

 #define ROS\_INFO(...) ROS\_LOG(::ros::console::levels::Info, ROSCONSOLE\_DEFAULT\_NAME, \_\_VA\_ARGS\_\_)

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:59:3: note: in expansion of macro ‘ROS\_INFO’

 ROS\_INFO("robot\_model : %s", robot\_model.c\_str());

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:60:37: error: ‘turning\_radius\_’ was not declared in this scope

 ROS\_INFO("turning\_radius\_ : %lf", turning\_radius\_);

 ^

/opt/ros/kinetic/include/ros/console.h:346:165: note: in definition of macro ‘ROSCONSOLE\_PRINT\_AT\_LOCATION\_WITH\_FILTER’

 ::ros::console::print(filter, \_\_rosconsole\_define\_location\_\_loc.logger\_, \_\_rosconsole\_define\_location\_\_loc.level\_, \_\_FILE\_\_, \_\_LINE\_\_, \_\_ROSCONSOLE\_FUNCTION\_\_, \_\_VA\_ARGS\_\_)

 ^

/opt/ros/kinetic/include/ros/console.h:379:7: note: in expansion of macro ‘ROSCONSOLE\_PRINT\_AT\_LOCATION’

 ROSCONSOLE\_PRINT\_AT\_LOCATION(\_\_VA\_ARGS\_\_); \

 ^

/opt/ros/kinetic/include/ros/console.h:561:35: note: in expansion of macro ‘ROS\_LOG\_COND’

 #define ROS\_LOG(level, name, ...) ROS\_LOG\_COND(true, level, name, \_\_VA\_ARGS\_\_)

 ^

/opt/ros/kinetic/include/rosconsole/macros\_generated.h:110:23: note: in expansion of macro ‘ROS\_LOG’

 #define ROS\_INFO(...) ROS\_LOG(::ros::console::levels::Info, ROSCONSOLE\_DEFAULT\_NAME, \_\_VA\_ARGS\_\_)

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:60:3: note: in expansion of macro ‘ROS\_INFO’

 ROS\_INFO("turning\_radius\_ : %lf", turning\_radius\_);

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:61:43: error: ‘front\_distance\_limit\_’ was not declared in this scope

 ROS\_INFO("front\_distance\_limit\_ = %lf", front\_distance\_limit\_);

 ^

/opt/ros/kinetic/include/ros/console.h:346:165: note: in definition of macro ‘ROSCONSOLE\_PRINT\_AT\_LOCATION\_WITH\_FILTER’

 ::ros::console::print(filter, \_\_rosconsole\_define\_location\_\_loc.logger\_, \_\_rosconsole\_define\_location\_\_loc.level\_, \_\_FILE\_\_, \_\_LINE\_\_, \_\_ROSCONSOLE\_FUNCTION\_\_, \_\_VA\_ARGS\_\_)

 ^

/opt/ros/kinetic/include/ros/console.h:379:7: note: in expansion of macro ‘ROSCONSOLE\_PRINT\_AT\_LOCATION’

 ROSCONSOLE\_PRINT\_AT\_LOCATION(\_\_VA\_ARGS\_\_); \

 ^

/opt/ros/kinetic/include/ros/console.h:561:35: note: in expansion of macro ‘ROS\_LOG\_COND’

 #define ROS\_LOG(level, name, ...) ROS\_LOG\_COND(true, level, name, \_\_VA\_ARGS\_\_)

 ^

/opt/ros/kinetic/include/rosconsole/macros\_generated.h:110:23: note: in expansion of macro ‘ROS\_LOG’

 #define ROS\_INFO(...) ROS\_LOG(::ros::console::levels::Info, ROSCONSOLE\_DEFAULT\_NAME, \_\_VA\_ARGS\_\_)

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:61:3: note: in expansion of macro ‘ROS\_INFO’

 ROS\_INFO("front\_distance\_limit\_ = %lf", front\_distance\_limit\_);

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:62:42: error: ‘side\_distance\_limit\_’ was not declared in this scope

 ROS\_INFO("side\_distance\_limit\_ = %lf", side\_distance\_limit\_);

 ^

/opt/ros/kinetic/include/ros/console.h:346:165: note: in definition of macro ‘ROSCONSOLE\_PRINT\_AT\_LOCATION\_WITH\_FILTER’

 ::ros::console::print(filter, \_\_rosconsole\_define\_location\_\_loc.logger\_, \_\_rosconsole\_define\_location\_\_loc.level\_, \_\_FILE\_\_, \_\_LINE\_\_, \_\_ROSCONSOLE\_FUNCTION\_\_, \_\_VA\_ARGS\_\_)

 ^

/opt/ros/kinetic/include/ros/console.h:379:7: note: in expansion of macro ‘ROSCONSOLE\_PRINT\_AT\_LOCATION’

 ROSCONSOLE\_PRINT\_AT\_LOCATION(\_\_VA\_ARGS\_\_); \

 ^

/opt/ros/kinetic/include/ros/console.h:561:35: note: in expansion of macro ‘ROS\_LOG\_COND’

 #define ROS\_LOG(level, name, ...) ROS\_LOG\_COND(true, level, name, \_\_VA\_ARGS\_\_)

 ^

/opt/ros/kinetic/include/rosconsole/macros\_generated.h:110:23: note: in expansion of macro ‘ROS\_LOG’

 #define ROS\_INFO(...) ROS\_LOG(::ros::console::levels::Info, ROSCONSOLE\_DEFAULT\_NAME, \_\_VA\_ARGS\_\_)

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:62:3: note: in expansion of macro ‘ROS\_INFO’

 ROS\_INFO("side\_distance\_limit\_ = %lf", side\_distance\_limit\_);

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:65:3: error: ‘right\_joint\_encoder\_’ was not declared in this scope

 right\_joint\_encoder\_ = 0.0;

 ^

/home/labpc/catkin\_ws/src/turtlebot3\_simulations/turtlebot3\_gazebo/src/gazebo\_ros\_turtlebot3.cpp:66:3: error: ‘priv\_right\_joint\_encoder\_’ was not declared in this scope

 priv\_right\_joint\_encoder\_ = 0.0;

 ^