



```
varsha@varsha-Vostro-3590:~$ roslaunch husky_gazebo husky_playpen.launch
... logging to /home/varsha/.ros/log/8b614126-efb0-11eb-be3b-ac1203c940e6/roslaunch-varsha-Vostro-3590-3173.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://varsha-Vostro-3590:35095/
```

SUMMARY

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PARAMETERS

```
* /ekf_localization/base_link_frame: base_link
* /ekf_localization/frequency: 50
* /ekf_localization/imu0: imu/data
* /ekf_localization/imu0_config: [False, False, Fa...
* /ekf_localization/imu0_differential: True
* /ekf_localization/imu0_queue_size: 10
* /ekf_localization/imu0_remove_gravitational_acceleration: True
* /ekf_localization/odom0: husky_velocity_co...
* /ekf_localization/odom0_config: [False, False, Fa...
* /ekf_localization/odom0_differential: False
* /ekf_localization/odom0_queue_size: 10
* /ekf_localization/odom_frame: odom
* /ekf_localization/two_d_mode: True
* /ekf_localization/world_frame: odom
* /gazebo/enable_ros_network: True
* /husky_joint_publisher/publish_rate: 50
* /husky_joint_publisher/type: joint_state_contr...
* /husky_velocity_controller/angular/z/has_acceleration_limits: True
* /husky_velocity_controller/angular/z/has_velocity_limits: True
* /husky_velocity_controller/angular/z/max_acceleration: 6.0
* /husky_velocity_controller/angular/z/max_velocity: 2.0
* /husky_velocity_controller/base_frame_id: base_link
* /husky_velocity_controller/cmd_vel_timeout: 0.25
* /husky_velocity_controller/enable_odom_tf: False
* /husky_velocity_controller/estimate_velocity_from_position: False
* /husky_velocity_controller/left_wheel: ['front_left_whee...
* /husky_velocity_controller/linear/x/has_acceleration_limits: True
* /husky_velocity_controller/linear/x/has_velocity_limits: True
* /husky_velocity_controller/linear/x/max_acceleration: 3.0
* /husky_velocity_controller/linear/x/max_velocity: 1.0
* /husky_velocity_controller/pose_covariance_diagonal: [0.001, 0.001, 0....
* /husky_velocity_controller/publish_rate: 50
* /husky_velocity_controller/right_wheel: ['front_right_whe...
* /husky_velocity_controller/twist_covariance_diagonal: [0.001, 0.001, 0....
* /husky_velocity_controller/type: diff_drive_contro...
* /husky_velocity_controller/velocity_rolling_window_size: 2
* /husky_velocity_controller/wheel_radius_multiplier: 1.0
* /husky_velocity_controller/wheel_separation_multiplier: 1.875
* /joy_teleop/joy_node/autorepeat_rate: 20
* /joy_teleop/joy_node/deadzone: 0.1
* /joy_teleop/joy_node/dev: /dev/input/ps4
* /joy_teleop/teleop_twist_joy/axis_angular: 0
```