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yahboom@VM: ~/roscourse_sim_ws
yahboom@VM: ~/roscourse_sim_ws/src/my_robot/urdf$ ros2 run robot_state_publisher robot_state_publisher --ros-args -p robot_description:="$(xacro my_robot.urdf.xacro)"
[FATAL] [1712941947.944205374] [robot_state_publisher]: robot_description parameter must not be empty
terminate called after throwing an instance of 'std::runtime_error'
what(): robot_description parameter must not be empty
yahboom@VM:~/roscourse_sim_ws/src/my_robot/urdf$ ros2 run robot_state_publisher robot_state_publisher --ros-args -p robot_description:="$(xacro my_robot.urdf.xacro)"
--ros-args: command not found
yahboom@VM:~/roscourse_sim_ws/src/my_robot/urdf$ ros2 run robot_state_publisher robot_state_publisher --ros-args -p robot_description:="$(xacro my_robot.urdf.xacro)"
terminate called after throwing an instance of 'rclcpp::exceptions::UnknownROSArgsError'
what(): found unknown ROS arguments: 'version="1.0"', '?>', '<!--', '=====  
=====', '--->', '<!--', '|', 'This', 'document', 'was', 'autogenerated', 'by', 'xacro', 'from', 'my_robot.urdf.xacro', '|', '--->', '<!--', '|', 'EDITING', 'THIS', 'FILE', 'BY', 'HAND', 'IS', 'NOT', 'RECOMMENDED', '|', '--->', '<!--', '=====  
=====', '--->', '<robot', 'name="my_robot">', '#base', 'values', '#added', '#added', '#added', '#wheel', 'values', '#added', '#added', '#inertia', 'matrix', 'of', 'box', '#', 'height', '=', 'ly', 'width', '=', 'lx', 'depth', '=', 'lz', '#inertia', 'matrix', 'of', 'cylinder', '#inertia', 'matrix', 'of', 'sphere', 'material', 'name="green">', 'color', 'rgba="0', '0.6', '0', '1"/>', 'material', 'name="white">', 'color', 'rgba="1', '1', '1', '1"/>', 'material', 'name="gray">', 'color', 'rgba="0.7', '0.7', '0.7', '0.7"/>', 'material', 'name="base_link">', 'visual', 'geometry', 'box', 'size="0.6', '0.4', '0.2"/>'
yahboom@VM: ~/94x5
Processing triggers for mime-support (3.64ubuntu1) ...
Processing triggers for hicolor-icon-theme (0.17-2) ...
Processing triggers for gnome-menus (3.36.0-1ubuntu1) ...
yahboom@VM:~$ ros2 launch gazebo_ros gazebo.launch.py
[INFO] [launch]: All log files can be found below /home/yahboom/.ros/log/2024-04-13-01-13-33-375833-VM-8748
yahboom@VM: ~/roscourse_sim_ws 94x6
- frame does not exist
[rviz2-2] at line 133 in /tmp/binarydeb/ros-foxy-tf2-0.13.14/src/buffer_core.cpp
[rviz2-2] Warning: Invalid frame ID "right_wheel" passed to canTransform argument source_frame
- frame does not exist
[rviz2-2] at line 133 in /tmp/binarydeb/ros-foxy-tf2-0.13.14/src/buffer_core.cpp
[rviz2-2] Warning: Invalid frame ID "left_wheel" passed to canTransform argument source_frame
- frame does not exist
```

