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Terminal
Figure 1
wiki
ipedia
with
port for tf2
ect to contin
In each she
1/setup.s
trans
form_publ
static t
static trans
roll, pitch,
transform data

ald@aldo-MacBookPro: ~
roscore http://... x /home/aldo/cat... x aldo@aldo-Mac... x aldo@aldo-Mac... x
in RPY (radian) [0.000, 0.000, -2.770]
in RPY (degree) [0.000, 0.000, -158.733]
At time 1580286752.630
- Translation: [0.037, -0.002, 0.010]
- Rotation: in Quaternion [0.000, 0.000, 0.983, -0.186]
in RPY (radian) [0.000, 0.000, -2.767]
in RPY (degree) [0.000, 0.000, -158.559]
At time 1580286753.615
- Translation: [0.037, -0.002, 0.010]
- Rotation: in Quaternion [0.000, 0.000, 0.982, -0.187]
in RPY (radian) [0.000, 0.000, -2.766]
in RPY (degree) [0.000, 0.000, -158.476]
At time 1580286754.550
- Translation: [0.037, -0.002, 0.010]
- Rotation: in Quaternion [0.000, 0.000, 0.983, -0.186]
in RPY (radian) [0.000, 0.000, -2.768]
in RPY (degree) [0.000, 0.000, -158.566]
At time 1580286755.606
- Translation: [0.037, -0.002, 0.010]
- Rotation: in Quaternion [0.000, 0.000, 0.983, -0.184]
in RPY (radian) [0.000, 0.000, -2.770]
in RPY (degree) [0.000, 0.000, -158.736]

/home/aldo/catkin_ws/src/turtlebot3/turtlebot3_teleop/launch/turtlebot3_teleop
space key, s : force stop
CTRL-C to quit
currently: linear vel 0.0 angular vel -0.2
currently: linear vel 0.0 angular vel -0.3
currently: linear vel 0.0 angular vel -0.4
currently: linear vel 0.0 angular vel -0.5
currently: linear vel 0.0 angular vel 0.0
currently: linear vel 0.0 angular vel -0.1
currently: linear vel 0.0 angular vel -0.2
currently: linear vel 0.0 angular vel -0.3
currently: linear vel 0.0 angular vel -0.4
currently: linear vel 0.0 angular vel -0.5
currently: linear vel 0.0 angular vel 0.0
currently: linear vel 0.0 angular vel -0.1
currently: linear vel 0.0 angular vel -0.2
currently: linear vel 0.0 angular vel -0.3
currently: linear vel 0.0 angular vel -0.4
currently: linear vel 0.0 angular vel -0.5
currently: linear vel 0.0 angular vel 0.0

/home/pi/catkin_ws/src/turtlebot3/turtlebot3_brainup/launch/turtlebot3_robot.launch
[INFO] [1580286063.528114]: Setup publisher on odom [nav_msgs/Odometry]
[INFO] [1580286063.542950]: Setup publisher on joint_states [sensor_msgs/JointState]
[INFO] [1580286063.562811]: Setup publisher on battery_state [sensor_msgs/BatteryState]
[INFO] [1580286063.576302]: Setup publisher on magnetic_field [sensor_msgs/MagneticField]
[INFO] [1580286066.938797]: Setup publisher on tf [tf/tfMessage]
[INFO] [1580286066.987179]: Note: subscribe buffer size is 1024 bytes
[INFO] [1580286066.989055]: Setup subscriber on cmd_vel [geometry_msgs/Twist]
[INFO] [1580286067.013517]: Setup subscriber on sound [turtlebot3_msgs/Sound]
[INFO] [1580286067.041849]: Setup subscriber on motor_power [std_msgs/Bool]
[INFO] [1580286067.069098]: Setup subscriber on reset [std_msgs/Empty]
[INFO] [1580286067.099384]: Setup TF on Odometry [odom]
[INFO] [1580286067.105920]: Setup TF on IMU [imu_link]
[INFO] [1580286067.112515]: Setup TF on MagneticField [mag_link]
[INFO] [1580286067.119094]: Setup TF on JointState [base_link]
[INFO] [1580286067.132709]: -----
[INFO] [1580286067.139349]: Connected to OpenCR board!
[INFO] [1580286067.145733]: This core(v1.2.3) is compatible with TB3 Burger
[INFO] [1580286067.150947]: .....
[INFO] [1580286067.154764]: Start Calibration of Gyro
[INFO] [1580286069.659792]: Calibration End
```