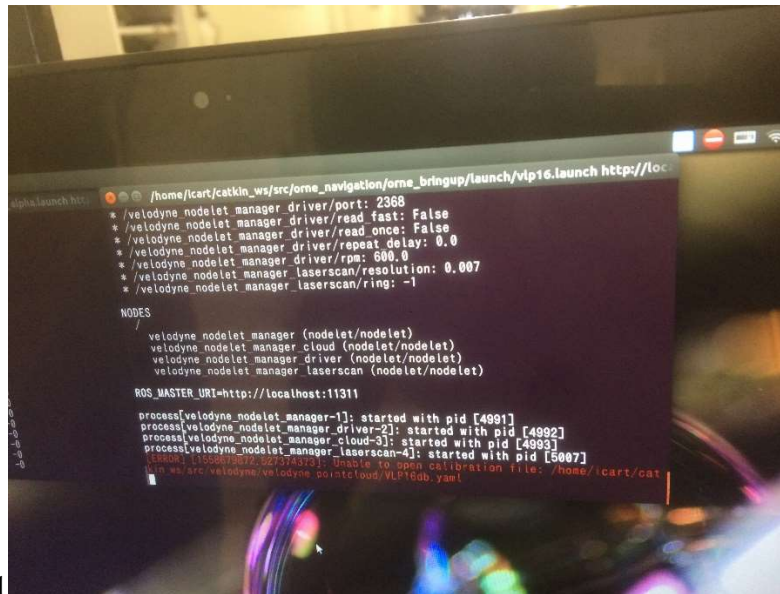


/roslaunch velodyne_pointcloud VLP16_points.launch

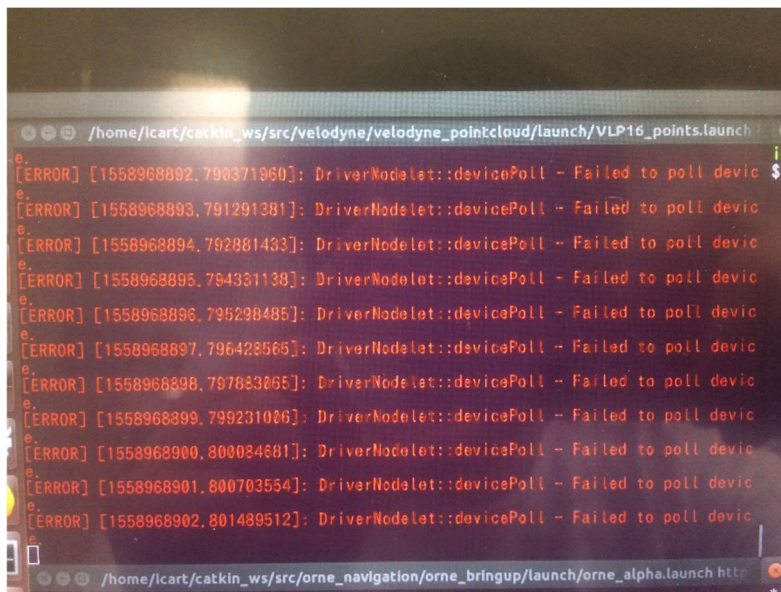
Velodyne1



1

原因:yaml ファイルがない

Velodyne:2



原因 1:PC と Velodyne がつながっていない、ethere ケーブルが PC から Velodyne につながっているか確認

原因 2:velodyne のネットワーク設定ができていない

/roslaunch orne_navigation_executor build_map_teleop.launch

```
starting new master
$ 
by path event10 event13 event16 event17 event4 ev
event0 event11 event14 event17 event4 ev
icart@icart-ThinkPad-P40-Yoga:~$ 
$ 
starting new master
$ 
/home/icart/catkin_ws/src/orne_navigation/orne_navigation_executor/launch/build_map
* /waypoints_saver/filename: /home/icart/catki...
* /waypoints_saver/save_joy_button: 0
NODES
/
joy_node (joy/joy_node)
rviz (rviz/rviz)
slam_gmapping (gmapping/slam_gmapping)
teleop_twist_joy (teleop_twist_joy/teleop_node)
waypoints_saver (fulanghua_waypoints_nav/waypoints_saver)
ROS_MASTER_URI=http://localhost:11311
process[waypoints_saver-1]: started with pid [30443]
process[joy_node-2]: started with pid [30444]
process[teleop_twist_joy-3]: started with pid [30460]
process[slam_gmapping-4]: started with pid [30471]
process[rviz-5]: started with pid [30504]
[rviz-5] process has died [pid 30504, exit code -11, cmd /opt/ros/kinetic/lib/rv
iz/rviz -d /home/icart/catkin_ws/src/orne_navigation/orne_navigation_executor/rv
iz/cfg/x.rviz --name=rviz --log:=/home/icart/.ros/log/56524ce4-80fb-11e9-b6d2-1
4abc575fee/rviz-5.log].
log file: /home/icart/.ros/log/56524ce4-80fb-11e9-b6d2-14abc575fee/rviz-5*.log
```

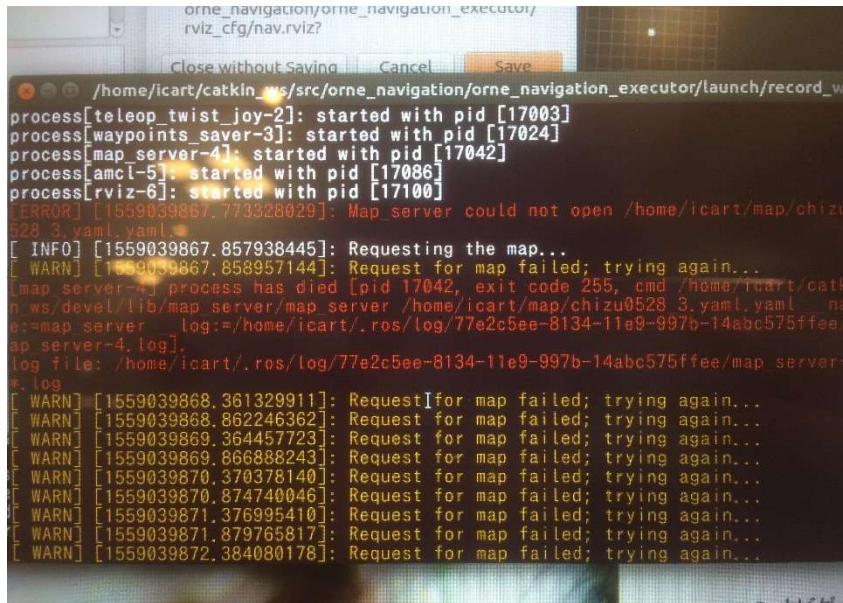
原因:不明

起動しなおしたら出来た

```
[INFO] [1559012399.137456922]: Commands for joints: 0, -0
[INFO] [1559012399.147453493]: Commands for joints: 0, -0
[INFO] [1559012399.157437254]: Commands for joints: 0, -0
[INFO] [1559012399.167639730]: Commands for joints: 0, -0
/home/icart/catkin_ws/src/orne_navigation/orne_navigation_executor/launch/build_map
* /waypoints_saver/filename: /home/icart/catki...
* /waypoints_saver/save_joy_button: 0
NODES
/
joy_node (joy/joy_node)
rviz (rviz/rviz)
slam_gmapping (gmapping/slam_gmapping)
teleop_twist_joy (teleop_twist_joy/teleop_node)
waypoints_saver (fulanghua_waypoints_nav/waypoints_saver)
ROS_MASTER_URI=http://localhost:11311
process[waypoints_saver-1]: started with pid [12757]
process[joy_node-2]: started with pid [12758]
process[teleop_twist_joy-3]: started with pid [12770]
process[slam_gmapping-4]: started with pid [12781]
process[rviz-5]: started with pid [12804]
[ERROR] [1559012244.178070644]: Couldn't open joystick /dev/input/js0. Will retr
y every second.
Laser Pose= 0.110219 0.00436769 -0.0870623
Laser Pose= 0.110434 0.0113372 -0.0415002
Registering Scans:Done
```

原因:ジョイスティックが/dev/input/にない

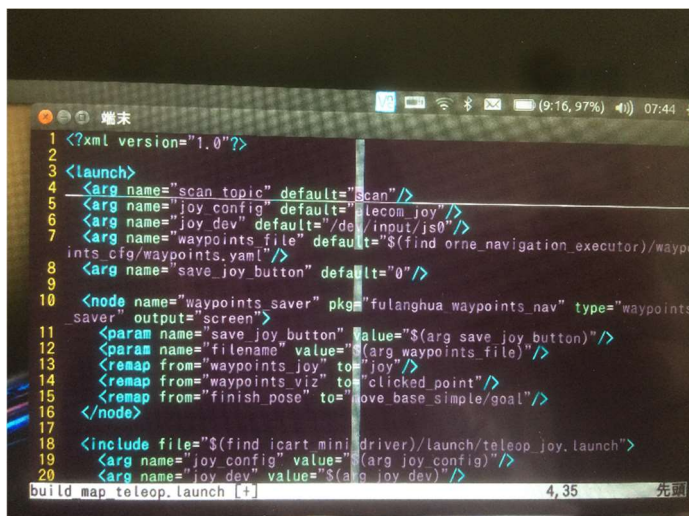
/record_waypoints



マップ名指定時.yamlをつける必要なし

Orne_alpha リモートとの違い

- orne_navigation_executor localization.launch リマップが必要
Amcl パッケージ内に
`<remap from="/scan" to="/vel_scan"/>`
を追加する。
- orne_navigation_executor build_map_teleop.launch 引数 scan_topic の変更
“build_map_teleop.launch”4 行目“scan”から“vel_scan”に変更する



```
1 <?xml version="1.0"?>
2
3 <launch>
4   <arg name="scan_topic" default="vel_scan"/>
5   <arg name="joy_config" default="elecom_joy"/>
6   <arg name="joy_dev" default="/dev/input/js0"/>
7   <arg name="waypoints_file" default="$(find orne_navigation_executor)/way
8     ints_cfg/waypoints.yaml"/>
9   <arg name="save_joy_button" default="0"/>
10  <node name="waypoints_saver" pkg="filanghua_waypoints_nav" type="waypoint
11    _saver" output="screen">
12    <param name="save_joy_button" value="$(arg save_joy_button)"/>
13    <param name="filename" value="$(arg waypoints_file)"/>
14    <remap from="waypoints_joy" to="joy"/>
15    <remap from="waypoints_viz" to="clicked_point"/>
16    <remap from="finish_pose" to="move_base_simple/goal"/>
17  </node>
18  <include file="$(find icart_mini_driver)/launch/teleop_joy.launch">
19    <arg name="joy_config" value="$(arg joy_config)"/>
20    <arg name="joy_dev" value="$(arg joy_dev)"/>
21  </include>
22</launch>
```

build map teleop.launch [4, 38]

自立走行停止

- ・狭い幅にはまると停止する

81cm の幅無理