

```
CMake Error at chapter2_tutorials/CMakeLists.txt:150 (add_executable):
  add_executable cannot create target "20185917" because another target
  with
  the same name already exists. The existing target is an executable
  created
  in source directory
  "/home/bender/2020year_class/ROS/2020rosws/src/chapter2_tutorials". See
  documentation for policy CMP0002 for more details.
```

```
CMake Error at chapter2_tutorials/CMakeLists.txt:151 (add_executable):
  add_executable cannot create target "fuhaoran" because another target
  with
  the same name already exists. The existing target is an executable
  created
  in source directory
  "/home/bender/2020year_class/ROS/2020rosws/src/chapter2_tutorials". See
  documentation for policy CMP0002 for more details.
```

我之前有用过20185917和fuhaoran做节点名字，编译生成有可执行的菱形的节点，虽然我后来改了，但是lib里的节点没有删，我直接把工作空间里面除了src删掉我试了一遍并没有成功，发现cmakelist里面add\_dependencies部分写的add\_executable，赶紧改回来

```
/home/bender/2020year_class/ROS/2020rosws/src/chapter2_tutorials/src/chapter2homeworkfhr_a.cpp:21:8: error: stray '\357' in program
```

输入了中文的标点符号

ros里面可以用的消息类型在roswiki里面可以查看 直接搜rosmmsg wiki 因为像int是非法的，得int32这样

```
make[2]: 警告：检测到时钟错误。您的创建可能是不完整的。
make[2]: 警告：检测到时钟错误。您的创建可能是不完整的。
make[2]: 警告：检测到时钟错误。您的创建可能是不完整的。
```

原因可能是：服务器上的文件最后修改时间比当前时钟要晚,就在那一刻我发现右上角时间从2点多变成22:36  
find . -type f -exec touch {} ;即可

```
[ERROR] [1601131748.134167171]: received a tcpROS connection for a
nonexistent service [/fhrhomework_srv].
```

初始化服务不要放在while里面，不然会一直重新赋值，相当于开了又关，srv放到开头就行，有request才提供服务

```

import: not authorized `rospy' @ error/constitute.c/WriteImage/1028.
import: not authorized `cv2' @ error/constitute.c/WriteImage/1028.
import: not authorized `np' @ error/constitute.c/WriteImage/1028.
import: not authorized `copy' @ error/constitute.c/WriteImage/1028.
import: not authorized `math' @ error/constitute.c/WriteImage/1028.
import: not authorized `roslib' @ error/constitute.c/WriteImage/1028.
from: can't read /var/mail/fingers.msg
/home/bender/fingerdecetionfhr/src/fingers/script/new.py: 行 20: threshold:
未找到命令
/home/bender/fingerdecetionfhr/src/fingers/script/new.py: 行 21: blurValue:
未找到命令
/home/bender/fingerdecetionfhr/src/fingers/script/new.py: 行 22:
bgSubThreshold: 未找到命令
/home/bender/fingerdecetionfhr/src/fingers/script/new.py: 行 23:
learningRate: 未找到命令
/home/bender/fingerdecetionfhr/src/fingers/script/new.py: 行 26:
isBgCaptured: 未找到命令
/home/bender/fingerdecetionfhr/src/fingers/script/new.py: 行 27:
triggerSwitch: 未找到命令
/home/bender/fingerdecetionfhr/src/fingers/script/new.py: 行 29: 未预期的符号
`(' 附近有语法错误
/home/bender/fingerdecetionfhr/src/fingers/script/new.py: 行 29: `def
printThreshold(thr):'

```

*#!/usr/bin/env python,申明这个文件是py代码,前面的/usr/bin/env是interpreter编译器路径*

```

Traceback (most recent call last):
  File "/home/bender/fingerdecetionfhr/src/fingers/script/new.py", line 9,
in <module>
    from fingers.msg import fingerdecetion
ImportError: No module named fingers.msg
和另一次的
CMake Error at
/opt/ros/kinetic/share/catkin/cmake/catkin_package_xml.cmake:54 (message):
  catkin_package_xml() package name 'fingers' in
  '/home/bender/fingerdecetionfhr/src/fingers/package.xml' does not match
  current PROJECT_NAME 'fingerdecetionfhr'. You must call project() with
  the
  same package name before.
Call Stack (most recent call first):
  /opt/ros/kinetic/share/catkin/cmake/catkin_package.cmake:99
(catkin_package_xml)
fingers/CMakeLists.txt:93 (catkin_package)

```

*我包名写错了,py文件里是这样的from fingers.msg import fingerdecetion, from后边是自己的包.msg, 也就是自己包的msg文件夹下, fingerdecetion是我的msg文件名fingerdecetion.msg 这个包名不是说src底下那个包名,他得是cmakelist里面project(fingers),这个名字,而且和xml的 fingers还得对上,不然就是上面第二个错误 改动py文件之后启动它不需要再次编译,直接roslaunch fingers new.py,roslaunch加包名加可执行文件名,文件记得给权限*

```
ERROR: Cannot load message class for [fingers/fingerdecetion]. Are your
messages built?
```

### source

```
CMake Error at /opt/ros/kinetic/share/catkin/cmake/catkinConfig.cmake:83
(find_package):
  Could not find a package configuration file provided by "PCL" with any of
  the following names:

    PCLConfig.cmake
    pcl-config.cmake

  Add the installation prefix of "PCL" to CMAKE_PREFIX_PATH or set
  "PCL_DIR"
  to a directory containing one of the above files.  If "PCL" provides a
  separate development package or SDK, be sure it has been installed.
Call Stack (most recent call first):
  turtlebotslam_obstacle_avoidance/CMakeLists.txt:12 (find_package)

-- Configuring incomplete, errors occurred!
See also "/home/bender/robocupsim2/build/CMakeFiles/CMakeOutput.log".
See also "/home/bender/robocupsim2/build/CMakeFiles/CMakeError.log".
```

下载的一个rgb视觉避障的工程,出这个错误,但我明明安了pcl库.于是locate PCLConfig.cmake,出来/usr/lib/x86\_64-linux-gnu/cmake/pcl/PCLConfig.cmake,把工程里面cmakelist的set(PCL\_DIR路径改了一下完事

```
Running command: "make -j8 -l8" in "/home/bender/robocupsim/build"
```

ros 8线程编译通过了,py不需要编译所以没有进度条,还有就是create\_ros\_pkg那个指令(具体不知道是啥了),可以直接在包里生成cmakelist和xml

```
/home/bender/jindapingrobocup/src/turtlebot_mpepc-
master/mpepc_local_planner/include/mpepc_local_planner/mpepc_planner_ros.h:
67:21: fatal error: nlopt.hpp: 没有那个文件或目录
compilation terminated.
```

Nlopt是非线性优化自由/开放源码库,为许多不同的可用免费优化程序的在线以及其它各种算法的实现原提供了一个通用的接口。没库,sudo apt-get install libnlopt-dev完事

```
→ jindapingrobocup rosdep install rgbdsllam
ERROR: Rosdep cannot find all required resources to answer your query
Missing resource rgbdsllam
ROS path [0]=/opt/ros/kinetic/share/ros
ROS path [1]=/opt/ros/kinetic/share
```

从路径看出来并没有工作空间的`catkin_ws`的路径。`source devel/setup.bash`,如果这个工作空间又被我塞了一个新包进去还没编译可以先编译一下,(虽然缺依赖没过,但是可能已经有`cmakelist`什么的更新了,这个时候再`source`再安装依赖,再编译就可以过了)

`rviz`的图形界面有警告,找不到`costmap`和`globalmap`但订阅了,`rviz`也没有加载出代价地图,可能是因为没有装`navigation`,因为`navigation`没有默认安装。`sudo apt-get install navigation`

```
Traceback (most recent call last):
  File "how_to_run.py", line 6, in <module>
    from robot import Robot
  File "/home/book/sim_robocup/robot.py", line 123
    def get_box_position(self):
```

`tab` 空格对齐有问题

```
→ script python how_to_run.py
Traceback (most recent call last):
  File "how_to_run.py", line 9, in <module>
    from robocuppy.msg import vx_vth_sec
ImportError: No module named robocuppy.msg
```

别用`python`这个指令,这里面的`import`了自定义的`ros`的`msg`内容,咱们得用`roslaunch`包名加`xxx`点`py`

```
→ robocupsim roslaunch robocuppy how_to_run.py
[roslaunch] Couldn't find executable named how_to_run.py below
/home/bender/robocupall/robocupsim/src/robocuppy
[roslaunch] Found the following, but they're either not files,
[roslaunch] or not executable:
[roslaunch]
/home/bender/robocupall/robocupsim/src/robocuppy/script/how_to_run.py
```

`py`文件属性给给下可执行权限

```
rospy.exceptions.ROSError: rospy.init_node() has already been called
with different arguments: ('robot',
['/home/bender/robocupall/robocupsim/src/robocuppy/script/how_to_run.py'],
False, None, False, False)
```

一个py文件好像只能有一个init节点,相当于ros::init一次,rospy.Publisher相当于ros::Publisher

```
vx_vth_sec vx_vth_sec_test()  
                ^  
SyntaxError: invalid syntax
```

语法错了,这里的vx\_vth\_sec是我写的msg类型,我应该这么声明vx\_vth\_sec\_test:vx\_vth\_sec\_test = vx\_vth\_sec()