ros2 launch irobot_create_gazebo create3.launch.py
[INFO] [launch]: All log files can be found below /home/ubuntu/.ros/log/2021-10-25-12-26-41-641090-c3desktop-31218
[INFO] [launch]: Default logging verbosity is set to INFO
[INFO] [joint_state_publisher-1]: process started with pid [31222]
[INFO] [robot_state_publisher-2]: process started with pid [31224]
[INFO] [rviz2-3]: process started with pid [31226]
[INFO] [spawner.py-4]: process started with pid [31228]
[INFO] [gzserver-5]: process started with pid [31231]
[INFO] [gzclient-6]: process started with pid [31242]
[INFO] [spawn_entity.py-7]: process started with pid [31245]
[INFO] [robot_state_publisher-8]: process started with pid [31247]
[INFO] [spawn_entity.py-9]: process started with pid [31249]
[INFO] [static_transform_publisher-10]: process started with pid [31259]
[INFO] [hazards_vector_publisher_node-11]: process started with pid [31265]
[INFO] [ir_intensity_vector_publisher_node-12]: process started with pid [31267]
[INFO] [motion_control-13]: process started with pid [31278]
[INFO] [wheel_status_publisher_node-14]: process started with pid [31289]
[INFO] [mock_publisher_node-15]: process started with pid [31291]
[robot_state_publisher-2] The root link base_link has an inertia specified in the URDF, but KDL does not support a root link with an inertia. As a workaround, you can add an extra dummy link to your URDF.
[robot_state_publisher-2] Link bump_front_center had 0 children
[robot_state_publisher-2] Link bump_front_left had 0 children
[robot_state_publisher-2] Link bump_front_right had 0 children
[robot_state_publisher-2] Link bump_left had 0 children
[robot_state_publisher-2] Link bump_right had 0 children
[robot_state_publisher-2] Link button_1 had 0 children
[robot_state_publisher-2] Link button_2 had 0 children
[robot_state_publisher-2] Link button_power had 0 children
[robot_state_publisher-2] Link cliff_front_left had 0 children
[robot_state_publisher-2] Link cliff_front_right had 0 children
[robot_state_publisher-2] Link cliff_side_left had 0 children
[robot_state_publisher-2] Link cliff_side_right had 0 children
[robot_state_publisher-2] Link front_caster_link had 0 children
[robot_state_publisher-2] Link imu_link had 0 children
[robot_state_publisher-2] Link ir_intensity_front_center_left had 0 children
[robot_state_publisher-2] Link ir_intensity_front_center_right had 0 children
[robot_state_publisher-2] Link ir_intensity_front_left had 0 children
[robot_state_publisher-2] Link ir_intensity_front_right had 0 children
[robot_state_publisher-2] Link ir_intensity_left had 0 children
[robot_state_publisher-2] Link ir_intensity_right had 0 children
[robot_state_publisher-2] Link ir_intensity_side_left had 0 children
[robot_state_publisher-2] Link ir_omni had 0 children
[robot_state_publisher-2] Link mouse had 0 children
[robot_state_publisher-2] Link wheel_drop_left had 1 children
[robot_state_publisher-2] Link left_wheel had 0 children
[robot_state_publisher-2] Link wheel_drop_right had 1 children
[robot_state_publisher-2] Link right_wheel had 0 children
[robot_state_publisher-2] [INFO] [1635179203.009572607] [robot_state_publisher]: got segment base_link
[robot_state_publisher-2] [INFO] [1635179203.009675850] [robot_state_publisher]: got segment bump_front_center
[robot_state_publisher-2] [INFO] [1635179203.009688889] [robot_state_publisher]: got segment bump_front_left
[robot_state_publisher-2] [INFO] [1635179203.009696949] [robot_state_publisher]: got segment bump_front_right
[robot_state_publisher-2] [INFO] [1635179203.009704206] [robot_state_publisher]: got segment bump_left
[robot_state_publisher-2] [INFO] [1635179203.009711335] [robot_state_publisher]: got segment bump_right

[robot_state_publisher-2] [INFO] [1635179203.009718238] [robot_state_publisher]: got segment button_1
[robot_state_publisher-2] [INFO] [1635179203.009725257] [robot_state_publisher]: got segment button_2
[robot_state_publisher-2] [INFO] [1635179203.009732218] [robot_state_publisher]: got segment button_power
[robot_state_publisher-2] [INFO] [1635179203.009739293] [robot_state_publisher]: got segment cliff_front_left
[robot_state_publisher-2] [INFO] [1635179203.009746254] [robot_state_publisher]: got segment cliff_front_right
[robot_state_publisher-2] [INFO] [1635179203.009753321] [robot_state_publisher]: got segment cliff_side_left
[robot_state_publisher-2] [INFO] [1635179203.009760284] [robot_state_publisher]: got segment cliff_side_right
[robot_state_publisher-2] [INFO] [1635179203.009767260] [robot_state_publisher]: got segment front_caster_link
[robot_state_publisher-2] [INFO] [1635179203.009774201] [robot_state_publisher]: got segment imu_link
[robot_state_publisher-2] [INFO] [1635179203.009781011] [robot_state_publisher]: got segment ir_intensity_front_center_left
[robot_state_publisher-2] [INFO] [1635179203.009788336] [robot_state_publisher]: got segment ir_intensity_front_center_right
[robot_state_publisher-2] [INFO] [1635179203.009795126] [robot_state_publisher]: got segment ir_intensity_front_left
[robot_state_publisher-2] [INFO] [1635179203.009802005] [robot_state_publisher]: got segment ir_intensity_front_right
[robot_state_publisher-2] [INFO] [1635179203.009808767] [robot_state_publisher]: got segment ir_intensity_left
[robot_state_publisher-2] [INFO] [1635179203.009815788] [robot_state_publisher]: got segment ir_intensity_right
[robot_state_publisher-2] [INFO] [1635179203.009822718] [robot_state_publisher]: got segment ir_intensity_side_left
[robot_state_publisher-2] [INFO] [1635179203.009829781] [robot_state_publisher]: got segment ir_omni
[robot_state_publisher-2] [INFO] [1635179203.009836613] [robot_state_publisher]: got segment left_wheel
[robot_state_publisher-2] [INFO] [1635179203.009843425] [robot_state_publisher]: got segment mouse
[robot_state_publisher-2] [INFO] [1635179203.009850404] [robot_state_publisher]: got segment right_wheel
[robot_state_publisher-2] [INFO] [1635179203.009857306] [robot_state_publisher]: got segment wheel_drop_left
[robot_state_publisher-2] [INFO] [1635179203.009864232] [robot_state_publisher]: got segment wheel_drop_right
[robot_state_publisher-8] The root link std_dock_link has an inertia specified in the URDF, but KDL does not support a root link with an inertia. As a workaround, you can add an extra dummy link to your URDF.
[robot_state_publisher-8] Link green_buoy_link had 0 children
[robot_state_publisher-8] Link halo_link had 0 children
[robot_state_publisher-8] Link red_buoy_link had 0 children
[robot_state_publisher-8] Link yellow_buoy_link had 0 children
[robot_state_publisher-8] [INFO] [1635179203.068544106] [dock_state_publisher]: got segment green_buoy_link
[robot_state_publisher-8] [INFO] [1635179203.068615829] [dock_state_publisher]: got segment halo_link
[robot_state_publisher-8] [INFO] [1635179203.068628196] [dock_state_publisher]: got segment red_buoy_link
[robot_state_publisher-8] [INFO] [1635179203.068636420] [dock_state_publisher]: got segment std_dock_link
[robot_state_publisher-8] [INFO] [1635179203.068643806] [dock_state_publisher]: got segment yellow_buoy_link
[static_transform_publisher-10] [INFO] [1635179203.130032993] [tf_odom_std_dock_link_publisher]: Spinning until killed publishing transform from 'odom' to 'std_dock_link'
[hazards_vector_publisher_node-11] [INFO] [1635179203.215457049] [hazards_vector_node]: Advertised topic: /hazard_detection
[hazards_vector_publisher_node-11] [INFO] [1635179203.217198697] [hazards_vector_node]: Subscription

to topic: _internal/bumper/event
[hazards_vector_publisher_node-11] [INFO] [1635179203.225747591] [hazards_vector_node]: Subscription to topic: _internal/cliff_front_left/event
[hazards_vector_publisher_node-11] [INFO] [1635179203.226988029] [hazards_vector_node]: Subscription to topic: _internal/cliff_front_right/event
[hazards_vector_publisher_node-11] [INFO] [1635179203.228329901] [hazards_vector_node]: Subscription to topic: _internal/cliff_side_left/event
[hazards_vector_publisher_node-11] [INFO] [1635179203.232069058] [hazards_vector_node]: Subscription to topic: _internal/cliff_side_right/event
[hazards_vector_publisher_node-11] [INFO] [1635179203.233789712] [hazards_vector_node]: Subscription to topic: _internal/wheel_drop/left_wheel/event
[hazards_vector_publisher_node-11] [INFO] [1635179203.267306540] [hazards_vector_node]: Subscription to topic: _internal/wheel_drop/right_wheel/event
[ir_intensity_vector_publisher_node-12] [INFO] [1635179203.352539479] [ir_intensity_vector_node]: Advertised topic: /ir_intensity
[wheel_status_publisher_node-14] [INFO] [1635179203.371126042] [wheel_status_publisher_node]: Advertised topic: /wheel_vels
[wheel_status_publisher_node-14] [INFO] [1635179203.394146131] [wheel_status_publisher_node]: Advertised topic: /wheel_ticks
[ir_intensity_vector_publisher_node-12] [INFO] [1635179203.431067244] [ir_intensity_vector_node]: Subscription to topic: _internal/ir_intensity_front_center_left
[ir_intensity_vector_publisher_node-12] [INFO] [1635179203.436325230] [ir_intensity_vector_node]: Subscription to topic: _internal/ir_intensity_front_center_right
[ir_intensity_vector_publisher_node-12] [INFO] [1635179203.443262042] [ir_intensity_vector_node]: Subscription to topic: _internal/ir_intensity_front_left
[ir_intensity_vector_publisher_node-12] [INFO] [1635179203.448283907] [ir_intensity_vector_node]: Subscription to topic: _internal/ir_intensity_front_right
[ir_intensity_vector_publisher_node-12] [INFO] [1635179203.456401374] [ir_intensity_vector_node]: Subscription to topic: _internal/ir_intensity_left
[ir_intensity_vector_publisher_node-12] [INFO] [1635179203.488296323] [ir_intensity_vector_node]: Subscription to topic: _internal/ir_intensity_right
[ir_intensity_vector_publisher_node-12] [INFO] [1635179203.496169853] [ir_intensity_vector_node]: Subscription to topic: _internal/ir_intensity_side_left
[mock_publisher_node-15] [INFO] [1635179203.607543370] [mock_publisher_node]: Advertised mocked topic: /interface_buttons
[mock_publisher_node-15] [INFO] [1635179203.626073311] [mock_publisher_node]: Advertised mocked topic: /slip_status
[mock_publisher_node-15] [INFO] [1635179203.641229212] [mock_publisher_node]: Advertised mocked topic: /kidnap_status
[mock_publisher_node-15] [INFO] [1635179203.648678473] [mock_publisher_node]: Advertised mocked topic: /battery_state
[mock_publisher_node-15] [INFO] [1635179203.653087617] [mock_publisher_node]: Advertised mocked topic: /stop_status
[mock_publisher_node-15] [INFO] [1635179203.671487506] [mock_publisher_node]: Subscription to topic: /hazard_detection
[mock_publisher_node-15] [INFO] [1635179203.677792107] [mock_publisher_node]: Subscription to topic: /odom
[mock_publisher_node-15] [INFO] [1635179203.688082850] [mock_publisher_node]: Subscription to topic: /cmd_lightring
[spawner.py-4] [INFO] [1635179204.366152488] [spawner_joint_state_broadcaster]: Waiting for /controller_manager services
[rviz2-3] [INFO] [1635179204.424121310] [rviz2]: Stereo is NOT SUPPORTED
[rviz2-3] [INFO] [1635179204.432905456] [rviz2]: OpenGl version: 3.1 (GLSL 1.4)
[rviz2-3] [INFO] [1635179204.678883957] [rviz2]: Stereo is NOT SUPPORTED
[spawn_entity.py-9] [INFO] [1635179204.866717996] [spawn_standard_dock]: Spawn Entity started
[spawn_entity.py-9] [INFO] [1635179204.878887319] [spawn_standard_dock]: Loading entity published on topic standard_dock_description

[spawn_entity.py-9] [INFO] [1635179204.889519829] [spawn_standard_dock]: Waiting for entity xml on standard_dock_description
[spawn_entity.py-9] [INFO] [1635179204.906182338] [spawn_standard_dock]: Waiting for service / spawn_entity, timeout = 5
[spawn_entity.py-9] [INFO] [1635179204.910433003] [spawn_standard_dock]: Waiting for service / spawn_entity
[rviz2-3] Warning: Invalid frame ID "left_wheel" passed to canTransform argument source_frame - frame does not exist
[rviz2-3]   at line 156 in /tmp/binarydeb/ros-galactic-tf2-0.17.2/src/buffer_core.cpp
[rviz2-3] Warning: Invalid frame ID "right_wheel" passed to canTransform argument source_frame - frame does not exist
[rviz2-3]   at line 156 in /tmp/binarydeb/ros-galactic-tf2-0.17.2/src/buffer_core.cpp
[rviz2-3] Warning: Invalid frame ID "wheel_drop_left" passed to canTransform argument source_frame - frame does not exist
[rviz2-3]   at line 156 in /tmp/binarydeb/ros-galactic-tf2-0.17.2/src/buffer_core.cpp
[rviz2-3] Warning: Invalid frame ID "wheel_drop_right" passed to canTransform argument source_frame - frame does not exist
[rviz2-3]   at line 156 in /tmp/binarydeb/ros-galactic-tf2-0.17.2/src/buffer_core.cpp
[rviz2-3] Warning: Invalid frame ID "left_wheel" passed to canTransform argument source_frame - frame does not exist
[rviz2-3]   at line 156 in /tmp/binarydeb/ros-galactic-tf2-0.17.2/src/buffer_core.cpp
[rviz2-3] Warning: Invalid frame ID "right_wheel" passed to canTransform argument source_frame - frame does not exist
[rviz2-3]   at line 156 in /tmp/binarydeb/ros-galactic-tf2-0.17.2/src/buffer_core.cpp
[rviz2-3] Warning: Invalid frame ID "wheel_drop_left" passed to canTransform argument source_frame - frame does not exist
[rviz2-3]   at line 156 in /tmp/binarydeb/ros-galactic-tf2-0.17.2/src/buffer_core.cpp
[rviz2-3] Warning: Invalid frame ID "wheel_drop_right" passed to canTransform argument source_frame - frame does not exist
[rviz2-3]   at line 156 in /tmp/binarydeb/ros-galactic-tf2-0.17.2/src/buffer_core.cpp
[spawn_entity.py-7] [INFO] [1635179205.178237584] [spawn_create3]: Spawn Entity started
[spawn_entity.py-7] [INFO] [1635179205.180007774] [spawn_create3]: Loading entity published on topic robot_description
[spawn_entity.py-7] [INFO] [1635179205.185669142] [spawn_create3]: Waiting for entity xml on robot_description
[spawn_entity.py-7] [INFO] [1635179205.188889312] [spawn_create3]: Waiting for service /spawn_entity, timeout = 5
[spawn_entity.py-7] [INFO] [1635179205.191958357] [spawn_create3]: Waiting for service /spawn_entity
[joint_state_publisher-1] [INFO] [1635179205.224500855] [joint_state_publisher]: Waiting for robot_description to be published on the robot_description topic...
[spawner.py-4] [INFO] [1635179206.392890023] [spawner_joint_state_broadcaster]: Waiting for / controller_manager services
[spawn_entity.py-9] [INFO] [1635179206.453063948] [spawn_standard_dock]: Calling service /spawn_entity
[spawn_entity.py-7] [INFO] [1635179206.456072030] [spawn_create3]: Calling service /spawn_entity
[spawn_entity.py-9] [INFO] [1635179206.670446618] [spawn_standard_dock]: Spawn status: SpawnEntity: Successfully spawned entity [standard_dock]
[spawn_entity.py-9] /opt/ros/galactic/lib/python3.8/site-packages/rclpy/qos.py:307: UserWarning: DurabilityPolicy.RMW_QOS_POLICY_DURABILITY_TRANSIENT_LOCAL is deprecated. Use DurabilityPolicy.TRANSIENT_LOCAL instead.
[spawn_entity.py-9]   warnings.warn(
[INFO] [spawn_entity.py-9]: process has finished cleanly [pid 31249]
[gzserver-5] [INFO] [1635179207.459041334] [cliff_front_left]: Started plugin
[gzserver-5] [INFO] [1635179207.544975998] [cliff_front_right]: Started plugin
[gzserver-5] [INFO] [1635179207.621793511] [cliff_side_left]: Started plugin
[gzserver-5] [INFO] [1635179207.725768545] [cliff_side_right]: Started plugin
[gzserver-5] [INFO] [1635179207.855178375] [bump_front_center_plugin]: Bumper plugin loaded correctly
[gzserver-5] [INFO] [1635179208.140044867] [ir_intensity_front_center_left]: Starting IR Emitter Plugin!

[gzserver-5] [INFO] [1635179208.212028462] [ir_intensity_front_center_right]: Starting IR Emitter Plugin!
[gzserver-5] [INFO] [1635179208.323741117] [ir_intensity_front_left]: Starting IR Emitter Plugin!
[gzserver-5] [INFO] [1635179208.383115657] [ir_intensity_front_right]: Starting IR Emitter Plugin!
[spawner.py-4] [INFO] [1635179208.415828852] [spawner_joint_state_broadcaster]: Waiting for /
controller_manager services
[gzserver-5] [INFO] [1635179208.472564109] [ir_intensity_left]: Starting IR Emitter Plugin!
[gzserver-5] [INFO] [1635179208.523818081] [ir_intensity_right]: Starting IR Emitter Plugin!
[spawn_entity.py-7] [INFO] [1635179208.555339394] [spawn_create3]: Spawn status: SpawnEntity:
Successfully spawned entity [create3]
[spawn_entity.py-7] /opt/ros/galactic/lib/python3.8/site-packages/rclpy/qos.py:307: UserWarning:
DurabilityPolicy.RMW_QOS_POLICY_DURABILITY_TRANSIENT_LOCAL is deprecated. Use
DurabilityPolicy.TRANSIENT_LOCAL instead.
[spawn_entity.py-7]   warnings.warn(
[gzserver-5] [INFO] [1635179208.617594466] [ir_intensity_side_left]: Starting IR Emitter Plugin!
[gzserver-5] [INFO] [1635179208.784141737] [wheel_drop_left_plugin]: Started wheel drop plugin
[gzserver-5] [INFO] [1635179208.825522389] [wheel_drop_right_plugin]: Started wheel drop plugin
[gzserver-5] [INFO] [1635179208.888500554] [gazebo_ros2_control]: Loading gazebo_ros2_control plugin
[gzserver-5] [INFO] [1635179208.988755188] [gazebo_ros2_control]: Starting gazebo_ros2_control plugin in
namespace: /
[gzserver-5] [INFO] [1635179208.990945314] [gazebo_ros2_control]: Starting gazebo_ros2_control plugin in
ros 2 node: gazebo_ros2_control
[gzserver-5] [INFO] [1635179208.992440701] [gazebo_ros2_control]: Loading parameter file /home/ubuntu/
create3desktop/create3_ws/install/irobot_create_control/share/irobot_create_control/config/control.yaml
[gzserver-5]
[INFO] [spawn_entity.py-7]: process has finished cleanly [pid 31245]
[gzserver-5] [INFO] [1635179209.027698486] [gazebo_ros2_control]: connected to service!!
robot_state_publisher
[gzserver-5] [INFO] [1635179209.031438822] [gazebo_ros2_control]: Recieved urdf from param server,
parsing...
[gzserver-5] [INFO] [1635179209.103803265] [gazebo_ros2_control]: Loading joint: left_wheel_joint
[gzserver-5] [INFO] [1635179209.103920936] [gazebo_ros2_control]:   Command:
[gzserver-5] [INFO] [1635179209.104007054] [gazebo_ros2_control]:   velocity
[gzserver-5] [INFO] [1635179209.104705671] [gazebo_ros2_control]:   State:
[gzserver-5] [INFO] [1635179209.104746680] [gazebo_ros2_control]:   velocity
[gzserver-5] [INFO] [1635179209.105221037] [gazebo_ros2_control]:   position
[gzserver-5] [INFO] [1635179209.114544619] [gazebo_ros2_control]: Loading joint: right_wheel_joint
[gzserver-5] [INFO] [1635179209.114746294] [gazebo_ros2_control]:   Command:
[gzserver-5] [INFO] [1635179209.114769213] [gazebo_ros2_control]:   velocity
[gzserver-5] [INFO] [1635179209.114793074] [gazebo_ros2_control]:   State:
[gzserver-5] [INFO] [1635179209.114809767] [gazebo_ros2_control]:   velocity
[gzserver-5] [INFO] [1635179209.114828846] [gazebo_ros2_control]:   position
[gzserver-5] [INFO] [1635179209.116166775] [gazebo_ros2_control]: Loading controller_manager
[gzserver-5] [WARN] [1635179209.318461878] [gazebo_ros2_control]: Desired controller update period
(0.01 s) is slower than the gazebo simulation period (0.001 s).
[gzserver-5] [INFO] [1635179209.319383661] [gazebo_ros2_control]: Loaded gazebo_ros2_control.
[gzserver-5] [INFO] [1635179209.371672876] [controller_manager]: Loading controller
'joint_state_broadcaster'
[gzserver-5] [INFO] [1635179209.429648802] [mouse_plugin]: Starting optical mouse plugin
[spawner.py-4] [INFO] [1635179209.491859473] [spawner_joint_state_broadcaster]: Loaded
joint_state_broadcaster
[gzserver-5] [INFO] [1635179209.513145464] [controller_manager]: Configuring controller
'joint_state_broadcaster'
[gzserver-5] [INFO] [1635179209.638389592] [ir_omni_plugin]: Starting ir opcode plugin
[gzserver-5] [INFO] [1635179209.900590270] [dock_status_publisher]: Starting ir opcode plugin
[spawner.py-4] [INFO] [1635179209.958518697] [spawner_joint_state_broadcaster]: Configured and started
joint_state_broadcaster
[spawner.py-4] /home/ubuntu/create3desktop/create3_ws/install/controller_manager/lib/controller_manager/

spawner.py:186: DeprecationWarning: 'spawner.py' is deprecated, please use 'spawner' (without .py extension)
[spawner.py-4]   warnings.warn(
[INFO] [spawner.py-4]: process has finished cleanly [pid 31228]
[INFO] [spawner.py-16]: process started with pid [31537]
[gzserver-5] [INFO] [1635179211.044611129] [controller_manager]: Loading controller 'diffdrive_controller'
[spawner.py-16] [INFO] [1635179211.408542446] [spawner_diffdrive_controller]: Loaded diffdrive_controller
[gzserver-5] [INFO] [1635179211.428182512] [controller_manager]: Configuring controller 'diffdrive_controller'
[spawner.py-16] [INFO] [1635179211.621007478] [spawner_diffdrive_controller]: Configured and started diffdrive_controller
[spawner.py-16] /home/ubuntu/create3desktop/create3_ws/install/controller_manager/lib/ controller_manager/spawner.py:186: DeprecationWarning: 'spawner.py' is deprecated, please use 'spawner' (without .py extension)
[spawner.py-16]   warnings.warn(
[INFO] [spawner.py-16]: process has finished cleanly [pid 31537]
[gzserver-5] gzserver: /opt/ros/galactic/include/rcppmath/clamp.hpp:41: constexpr const T& rcppmath::clamp(const T&, const T&, const T&) [with T = double]: Assertion `!(hi < lo)' failed.
[ERROR] [gzserver-5]: process has died [pid 31231, exit code 6, cmd 'gzserver -s libgazebo_ros_init.so -s libgazebo_ros_factory.so '].
[motion_control-13] [WARN] [1635179393.456470680] [motion_control]: Can't modify safety_override. Not implemented in sim yet
[mock_publisher_node-15] [INFO] [1635179393.494089528] [mock_publisher_node]: Lightring message received but it is not yet implemented in simulation
[mock_publisher_node-15] [INFO] [1635179393.515472592] [mock_publisher_node]: Lightring message received but it is not yet implemented in simulation
[mock_publisher_node-15] [INFO] [1635179393.570109049] [mock_publisher_node]: Lightring message received but it is not yet implemented in simulation
[mock_publisher_node-15] [INFO] [1635179393.617929686] [mock_publisher_node]: Lightring message received but it is not yet implemented in simulation
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