ch3 中make一步报错，具体好像是isometry3d等库函数没有声明？（报错... #14

⊘ Closed

gaoxiang12/**slambook2** Public

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xiaohuozi-code opened this issue Feb 24, 2021 · 3 comments

7

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ch3 中make一步报错，具体好像是isometry3d等库函数没有声明？（报错提示如下） #147

New issue

⊘ Closed   xiaohuozi-code opened this issue Feb 24, 2021 · 3 comments

xiaohuozi-code commented Feb 24, 2021 • edited ▾   ···

```
xiaotudou@xiaotudou-virtual-machine:~/slambook2/ch3/examples/build$ make
Scanning dependencies of target coordinateTransform
[ 25%] Building CXX object CMakeFiles/coordinateTransform.dir/coordinateTransform.cpp.o
[ 50%] Linking CXX executable coordinateTransform
[ 50%] Built target coordinateTransform
Scanning dependencies of target plotTrajectory
[ 75%] Building CXX object CMakeFiles/plotTrajectory.dir/plotTrajectory.cpp.o
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:12:28: error: 'Isometry3d' was not declared in this scope
 void DrawTrajectory(vector<Isometry3d, Eigen::aligned_allocator>);
                            ^~~~~~~~~~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:12:65: error: 'Isometry3d' was not declared in this scope
 void DrawTrajectory(vector<Isometry3d, Eigen::aligned_allocator>);
                            ^~~~~~~~~~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:12:65: error: template argument 1 is invalid
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:12:75: error: template argument 1 is invalid
 void DrawTrajectory(vector<Isometry3d, Eigen::aligned_allocator>);
                                                               ^
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:12:75: error: template argument 2 is invalid
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp: In function 'int main(int, char**)':
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:16:10: error: 'Isometry3d' was not declared in this scope
 vector<Isometry3d, Eigen::aligned_allocator> poses;
        ^~~~~~~~~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:16:47: error: type/value mismatch at argument 1 in template parameter list for 'template class Eigen::aligned_allocator'
 vector<Isometry3d, Eigen::aligned_allocator> poses;
        ^~~~~~~~~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:16:47: note: expected a type, got 'Isometry3d'
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:16:57: error: template argument 1 is invalid
 vector<Isometry3d, Eigen::aligned_allocator> poses;
        ^~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:16:57: error: template argument 2 is invalid
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:26:16: error: expected ';' before 'Twr'
 Isometry3d Twr(Quaterniond(qw, qx, qy, qz));
                ^~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:27:5: error: 'Twr' was not declared in this scope
 Twr.pretranslate(Vector3d(tx, ty, tz));
     ^~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:28:11: error: request for member 'push_back' in 'poses', which is of non-class type 'int'
 poses.push_back(Twr);
       ^~~~~~~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:30:34: error: request for member 'size' in 'poses', which is of non-class type 'int'
 cout << "read total " << poses.size() << " pose entries" << endl;
       ^~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp: At global scope:
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:38:28: error: 'Isometry3d' was not declared in this scope
 void DrawTrajectory(vector<Isometry3d, Eigen::aligned_allocator> poses) {
                            ^~~~~~~~~~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:38:65: error: 'Isometry3d' was not declared in this scope
 void DrawTrajectory(vector<Isometry3d, Eigen::aligned_allocator> poses) {
                            ^~~~~~~~~~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:38:65: error: template argument 1 is invalid
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:38:75: error: template argument 1 is invalid
 rawTrajectory(vector<Isometry3d, Eigen::aligned_allocator> poses) {
        ^~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:38:75: error: template argument 2 is invalid
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp: In function 'void DrawTrajectory(int)':
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:59:34: error: request for member 'size' in 'poses', which is of non-class type 'int'
 for (size_t i = 0; i < poses.size(); i++) {
                          ^~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:61:28: error: invalid types 'int[size_t {aka long unsigned int}]' for array subscript
 Vector3d Ow = poses[i].translation();
                    ^
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:62:28: error: invalid types 'int[size_t {aka long unsigned int}]' for array subscript
 Vector3d Xw = poses[i] * (0.1 * Vector3d(1, 0, 0));
                    ^
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:63:28: error: invalid types 'int[size_t {aka long unsigned int}]' for array subscript
 Vector3d Yw = poses[i] * (0.1 * Vector3d(0, 1, 0));
                    ^
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:64:28: error: invalid types 'int[size_t {aka long unsigned int}]' for array subscript
 Vector3d Zw = poses[i] * (0.1 * Vector3d(0, 0, 1));
                    ^
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:78:34: error: request for member 'size' in 'poses', which is of non-class type 'int'
 for (size_t i = 0; i < poses.size(); i++) {
                          ^~~~
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:81:24: error: invalid types 'int[size_t {aka long unsigned int}]' for array subscript
 auto p1 = poses[i], p2 = poses[i + 1];
                ^
/home/xiaotudou/slambook2/ch3/examples/plotTrajectory.cpp:83:18: error: 'p2' was not declared in this scope
 glVertex3d(p2.translation()[0], p2.translation()[1], p2.translation()[2]);
            ^~
CMakeFiles/plotTrajectory.dir/build.make:62: recipe for target 'CMakeFiles/plotTrajectory.dir/plotTrajectory.cpp.o' failed
make[2]: *** [CMakeFiles/plotTrajectory.dir/plotTrajectory.cpp.o] Error 1
CMakeFiles/Makefile2:104: recipe for target 'CMakeFiles/plotTrajectory.dir/all' failed
make[1]: *** [CMakeFiles/plotTrajectory.dir/all] Error 2
Makefile:83: recipe for target 'all' failed
make: *** [all] Error 2
```

⊘ xiaohuozi-code closed this as completed Feb 24, 2021

↻ xiaohuozi-code reopened this Feb 24, 2021

gaoxiang12 commented Feb 24, 2021   Owner   ···

把 <Eigen/Geometry> 引进来就可以了

👍 2   😄 1

xiaohuozi-code commented Feb 24, 2021   Author   ···

> 把 <Eigen/Geometry> 引进来就可以了

谢谢 已解决

⊘ gaoxiang12 closed this as completed Feb 27, 2021

Livesoso commented Nov 23, 2021   ···

我还以为版本的问题，气死，感谢感谢

Assignees

No one assigned

Labels

None yet

Projects

None yet

Milestone

No milestone

Development

No branches or pull requests

3 participants