ERROR LOG

d415

restart the system or USB3.0 problem. --》my device is USB3.0.checked through<lsusb>

Support??

when connected and use<lsusb>

>

Bus 002 Device 028: ID 8086:0adb Intel Corp.

Bus 002 Device 001: ID 1d6b:0003 Linux Foundation 3.0 root hub

Bus 001 Device 004: ID 0bda:b00a Realtek Semiconductor Corp.

Bus 001 Device 003: ID 04ca:7086 Lite-On Technology Corp.

Bus 001 Device 030: ID 046d:c542 Logitech, Inc.

Bus 001 Device 001: ID 1d6b:0002 Linux Foundation 2.0 root hub

>

restart the system to solve this problem???

rs-capture: /home/vicky/librealsense/src/pipeline/pipeline.cpp:84: void librealsense::pipeline::pipeline::unsafe\_start(std::shared\_ptr<librealsense::pipeline::config>): Assertion `profile->\_multistream.get\_profiles().size() > 0' failed.

Aborted (core dumped)

capture mistake

>

rs-capture: /home/vicky/librealsense/src/pipeline/pipeline.cpp:84: void librealsense::pipeline::pipeline::unsafe\_start(std::shared\_ptr<librealsense::pipeline::config>): Assertion `profile->\_multistream.get\_profiles().size() > 0' failed.

Aborted (core dumped)

>

when roslaunch

**roslaunch realsense2\_camera rs\_camera.launch align\_depth:=true**

... logging to /home/vicky/.ros/log/88d3af5c-c1df-11ea-a882-802bf9a9fbab/roslaunch-vicky-HP-Pavilion-Laptop-14-ce0xxx-16963.log

Checking log directory for disk usage. This may take a while.

Press Ctrl-C to interrupt

Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://vicky-HP-Pavilion-Laptop-14-ce0xxx:39797/

SUMMARY

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PARAMETERS

\* /camera/realsense2\_camera/accel\_fps: 250

\* /camera/realsense2\_camera/accel\_frame\_id: camera\_accel\_frame

\* /camera/realsense2\_camera/accel\_optical\_frame\_id: camera\_accel\_opti...

\* /camera/realsense2\_camera/align\_depth: True

\* /camera/realsense2\_camera/aligned\_depth\_to\_color\_frame\_id: camera\_aligned\_de...

\* /camera/realsense2\_camera/aligned\_depth\_to\_fisheye1\_frame\_id: camera\_aligned\_de...

\* /camera/realsense2\_camera/aligned\_depth\_to\_fisheye2\_frame\_id: camera\_aligned\_de...

\* /camera/realsense2\_camera/aligned\_depth\_to\_fisheye\_frame\_id: camera\_aligned\_de...

\* /camera/realsense2\_camera/aligned\_depth\_to\_infra1\_frame\_id: camera\_aligned\_de...

\* /camera/realsense2\_camera/aligned\_depth\_to\_infra2\_frame\_id: camera\_aligned\_de...

\* /camera/realsense2\_camera/allow\_no\_texture\_points: False

\* /camera/realsense2\_camera/base\_frame\_id: camera\_link

\* /camera/realsense2\_camera/calib\_odom\_file:

\* /camera/realsense2\_camera/clip\_distance: -2.0

\* /camera/realsense2\_camera/color\_fps: 30

\* /camera/realsense2\_camera/color\_frame\_id: camera\_color\_frame

\* /camera/realsense2\_camera/color\_height: 480

\* /camera/realsense2\_camera/color\_optical\_frame\_id: camera\_color\_opti...

\* /camera/realsense2\_camera/color\_width: 640

\* /camera/realsense2\_camera/depth\_fps: 30

\* /camera/realsense2\_camera/depth\_frame\_id: camera\_depth\_frame

\* /camera/realsense2\_camera/depth\_height: 480

\* /camera/realsense2\_camera/depth\_optical\_frame\_id: camera\_depth\_opti...

\* /camera/realsense2\_camera/depth\_width: 640

\* /camera/realsense2\_camera/device\_type:

\* /camera/realsense2\_camera/enable\_accel: False

\* /camera/realsense2\_camera/enable\_color: True

\* /camera/realsense2\_camera/enable\_depth: True

\* /camera/realsense2\_camera/enable\_fisheye1: False

\* /camera/realsense2\_camera/enable\_fisheye2: False

\* /camera/realsense2\_camera/enable\_fisheye: False

\* /camera/realsense2\_camera/enable\_gyro: False

\* /camera/realsense2\_camera/enable\_infra1: False

\* /camera/realsense2\_camera/enable\_infra2: False

\* /camera/realsense2\_camera/enable\_infra: False

\* /camera/realsense2\_camera/enable\_pointcloud: False

\* /camera/realsense2\_camera/enable\_pose: False

\* /camera/realsense2\_camera/enable\_sync: False

\* /camera/realsense2\_camera/filters:

\* /camera/realsense2\_camera/fisheye1\_frame\_id: camera\_fisheye1\_f...

\* /camera/realsense2\_camera/fisheye1\_optical\_frame\_id: camera\_fisheye1\_o...

\* /camera/realsense2\_camera/fisheye2\_frame\_id: camera\_fisheye2\_f...

\* /camera/realsense2\_camera/fisheye2\_optical\_frame\_id: camera\_fisheye2\_o...

\* /camera/realsense2\_camera/fisheye\_fps: 30

\* /camera/realsense2\_camera/fisheye\_frame\_id: camera\_fisheye\_frame

\* /camera/realsense2\_camera/fisheye\_height: 480

\* /camera/realsense2\_camera/fisheye\_optical\_frame\_id: camera\_fisheye\_op...

\* /camera/realsense2\_camera/fisheye\_width: 640

\* /camera/realsense2\_camera/gyro\_fps: 400

\* /camera/realsense2\_camera/gyro\_frame\_id: camera\_gyro\_frame

\* /camera/realsense2\_camera/gyro\_optical\_frame\_id: camera\_gyro\_optic...

\* /camera/realsense2\_camera/imu\_optical\_frame\_id: camera\_imu\_optica...

\* /camera/realsense2\_camera/infra1\_frame\_id: camera\_infra1\_frame

\* /camera/realsense2\_camera/infra1\_optical\_frame\_id: camera\_infra1\_opt...

\* /camera/realsense2\_camera/infra2\_frame\_id: camera\_infra2\_frame

\* /camera/realsense2\_camera/infra2\_optical\_frame\_id: camera\_infra2\_opt...

\* /camera/realsense2\_camera/infra\_fps: 30

\* /camera/realsense2\_camera/infra\_height: 480

\* /camera/realsense2\_camera/infra\_width: 640

\* /camera/realsense2\_camera/initial\_reset: False

\* /camera/realsense2\_camera/json\_file\_path:

\* /camera/realsense2\_camera/linear\_accel\_cov: 0.01

\* /camera/realsense2\_camera/odom\_frame\_id: camera\_odom\_frame

\* /camera/realsense2\_camera/pointcloud\_texture\_index: 0

\* /camera/realsense2\_camera/pointcloud\_texture\_stream: RS2\_STREAM\_COLOR

\* /camera/realsense2\_camera/pose\_frame\_id: camera\_pose\_frame

\* /camera/realsense2\_camera/pose\_optical\_frame\_id: camera\_pose\_optic...

\* /camera/realsense2\_camera/publish\_odom\_tf: True

\* /camera/realsense2\_camera/publish\_tf: True

\* /camera/realsense2\_camera/rosbag\_filename:

\* /camera/realsense2\_camera/serial\_no:

\* /camera/realsense2\_camera/tf\_publish\_rate: 0.0

\* /camera/realsense2\_camera/topic\_odom\_in: odom\_in

\* /camera/realsense2\_camera/unite\_imu\_method:

\* /camera/realsense2\_camera/usb\_port\_id:

\* /rosdistro: melodic

\* /rosversion: 1.14.6

NODES

/camera/

realsense2\_camera (nodelet/nodelet)

realsense2\_camera\_manager (nodelet/nodelet)

auto-starting new master

process[master]: started with pid [16974]

ROS\_MASTER\_URI=http://localhost:11311

setting /run\_id to 88d3af5c-c1df-11ea-a882-802bf9a9fbab

process[rosout-1]: started with pid [16986]

started core service [/rosout]

process[camera/realsense2\_camera\_manager-2]: started with pid [16989]

process[camera/realsense2\_camera-3]: started with pid [16994]

[ INFO] [1594297641.477694151]: Initializing nodelet with 8 worker threads.

[ INFO] [1594297641.998484834]: RealSense ROS v2.2.14

[ INFO] [1594297641.998602251]: Running with LibRealSense v2.35.2

[ INFO] [1594297642.021760092]:

09/07 13:27:22,033 WARNING [140096132912896] (types.cpp:49) info Serial Number not supported by the device!

terminate called after throwing an instance of 'rs2::invalid\_value\_error'

what(): info Serial Number not supported by the device!

**[camera/realsense2\_camera\_manager-2] process has died [pid 16989, exit code -6, cmd /opt/ros/melodic/lib/nodelet/nodelet manager \_\_name:=realsense2\_camera\_manager \_\_log:=/home/vicky/.ros/log/88d3af5c-c1df-11ea-a882-802bf9a9fbab/camera-realsense2\_camera\_manager-2.log].**

**log file: /home/vicky/.ros/log/88d3af5c-c1df-11ea-a882-802bf9a9fbab/camera-realsense2\_camera\_manager-2\*.log**