mahendran@bg-enhance:~$ cd catkin\_ws  
mahendran@bg-enhance:~/catkin\_ws$ source install\_isolated/setup.bash   
mahendran@bg-enhance:~/catkin\_ws$ cd src  
mahendran@bg-enhance:~/catkin\_ws/src$ cd sweep-ros  
mahendran@bg-enhance:~/catkin\_ws/src/sweep-ros$ cd launchmahendran@bg-enhance:~/catkin\_ws/src/sweep-ros/launch$ roslaunch sweep.launch  
... logging to /home/mahendran/.ros/log/f7bbfdba-449c-11e8-b606-a782b0d5ce85/roslaunch-bg-enhance-19606.log  
Checking log directory for disk usage. This may take awhile.  
Press Ctrl-C to interrupt  
Done checking log file disk usage. Usage is <1GB.  
  
started roslaunch server http://bg-enhance:32913/  
  
SUMMARY  
========  
  
PARAMETERS  
 \* /enable\_statistics: False  
 \* /pointcloud\_to\_laserscan/angle\_increment: 0.001  
 \* /pointcloud\_to\_laserscan/angle\_max: 3.14  
 \* /pointcloud\_to\_laserscan/angle\_min: -3.14  
 \* /pointcloud\_to\_laserscan/concurrency\_level: 1  
 \* /pointcloud\_to\_laserscan/max\_height: 1.0  
 \* /pointcloud\_to\_laserscan/min\_height: -1.0  
 \* /pointcloud\_to\_laserscan/range\_max: 10.0  
 \* /pointcloud\_to\_laserscan/range\_min: 0.0  
 \* /pointcloud\_to\_laserscan/scan\_time: 0.1  
 \* /pointcloud\_to\_laserscan/target\_frame: laser\_frame  
 \* /pointcloud\_to\_laserscan/transform\_tolerance: 0.001  
 \* /pointcloud\_to\_laserscan/use\_inf: True  
 \* /robot\_description: <...>  
 \* /rosdistro: indigo  
 \* /rosversion: 1.11.21  
 \* /sweep\_node/frame\_id: laser\_frame  
 \* /sweep\_node/rotation\_speed: 5  
 \* /sweep\_node/sample\_rate: 750  
 \* /sweep\_node/serial\_baudrate: 115200  
 \* /sweep\_node/serial\_port: /dev/ttyUSB0  
  
NODES  
  /  
    cartographer\_node (cartographer\_ros/cartographer\_node)  
    cartographer\_occupancy\_grid\_node (cartographer\_ros/cartographer\_occupancy\_grid\_node)  
    pointcloud\_to\_laserscan (pointcloud\_to\_laserscan/pointcloud\_to\_laserscan\_node)  
    robot\_state\_publisher (robot\_state\_publisher/robot\_state\_publisher)  
    rviz (rviz/rviz)  
    sweep\_node (sweep\_ros/sweep\_node)  
  
auto-starting new master  
process[master]: started with pid [19623]  
ROS\_MASTER\_URI=http://localhost:11311  
  
setting /run\_id to f7bbfdba-449c-11e8-b606-a782b0d5ce85  
process[rosout-1]: started with pid [19636]  
started core service [/rosout]  
process[robot\_state\_publisher-2]: started with pid [19647]  
process[sweep\_node-3]: started with pid [19652]  
process[pointcloud\_to\_laserscan-4]: started with pid [19653]  
process[cartographer\_node-5]: started with pid [19664]  
process[cartographer\_occupancy\_grid\_node-6]: started with pid [19686]  
process[rviz-7]: started with pid [19705]  
[ INFO] [1524230160.286459832]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer\_ros/configuration\_files/sweep.lua' for 'sweep.lua'.  
[ INFO] [1524230160.286838094]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/map\_builder.lua' for 'map\_builder.lua'.  
[ INFO] [1524230160.286895650]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/map\_builder.lua' for 'map\_builder.lua'.  
[ INFO] [1524230160.286976086]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/pose\_graph.lua' for 'pose\_graph.lua'.  
[ INFO] [1524230160.287018575]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/pose\_graph.lua' for 'pose\_graph.lua'.  
[ INFO] [1524230160.287227015]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/trajectory\_builder.lua' for 'trajectory\_builder.lua'.  
[ INFO] [1524230160.287273335]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/trajectory\_builder.lua' for 'trajectory\_builder.lua'.  
[ INFO] [1524230160.287344664]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/trajectory\_builder\_2d.lua' for 'trajectory\_builder\_2d.lua'.  
[ INFO] [1524230160.287387590]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/trajectory\_builder\_2d.lua' for 'trajectory\_builder\_2d.lua'.  
[ INFO] [1524230160.287513965]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/trajectory\_builder\_3d.lua' for 'trajectory\_builder\_3d.lua'.  
[ INFO] [1524230160.287814851]: I0420 14:16:00.000000 19664 configuration\_file\_resolver.cc:41] Found '/home/mahendran/catkin\_ws/install\_isolated/share/cartographer/configuration\_files/trajectory\_builder\_3d.lua' for 'trajectory\_builder\_3d.lua'.  
..."]:33: attempt to index global 'SPARSE\_POSE\_GRAPH' (a nil value)ailed: status == 0 (2 vs. 0) [string "include "map\_builder.lua"  
..."]:33: attempt to index global 'SPARSE\_POSE\_GRAPH' (a nil value)ameter\_dictionary.cc:83] Check failed: status == 0 (2 vs. 0) [string "include "map\_builder.lua"  
[ INFO] [1524230160.348656190]: expected rotation frequency: 5 (Hz)  
\*\*\* Check failure stack trace: \*\*\*  
    @     0x7f78f5e03daa  (unknown)  
    @     0x7f78f5e03ce4  (unknown)  
    @     0x7f78f5e036e6  (unknown)  
    @     0x7f78f5e06687  (unknown)  
    @           0x674d96  cartographer::common::(anonymous namespace)::CheckForLuaErrors()  
    @           0x675306  cartographer::common::LuaParameterDictionary::LuaParameterDictionary()  
    @           0x67548d  cartographer::common::LuaParameterDictionary::LuaParameterDictionary()  
    @           0x58d5a2  cartographer\_ros::LoadOptions()  
    @           0x58b8a3  cartographer\_ros::(anonymous namespace)::Run()  
    @           0x588e06  main  
    @     0x7f78f2281f45  (unknown)  
    @           0x58b6f7  (unknown)  
    @              (nil)  (unknown)  
[cartographer\_node-5] process has died [pid 19664, exit code -6, cmd /home/mahendran/catkin\_ws/install\_isolated/lib/cartographer\_ros/cartographer\_node -configuration\_directory /home/mahendran/catkin\_ws/install\_isolated/share/cartographer\_ros/configuration\_files -configuration\_basename sweep.lua \_\_name:=cartographer\_node \_\_log:=/home/mahendran/.ros/log/f7bbfdba-449c-11e8-b606-a782b0d5ce85/cartographer\_node-5.log].  
log file: /home/mahendran/.ros/log/f7bbfdba-449c-11e8-b606-a782b0d5ce85/cartographer\_node-5\*.log  
================================================================================REQUIRED process [rviz-7] has died!  
process has finished cleanly  
log file: /home/mahendran/.ros/log/f7bbfdba-449c-11e8-b606-a782b0d5ce85/rviz-7\*.log  
Initiating shutdown!  
================================================================================  
[rviz-7] killing on exit  
[cartographer\_occupancy\_grid\_node-6] killing on exit  
[pointcloud\_to\_laserscan-4] killing on exit  
[sweep\_node-3] killing on exit  
[robot\_state\_publisher-2] killing on exit  
[rosout-1] killing on exit  
[master] killing on exit  
shutting down processing monitor...  
... shutting down processing monitor complete  
done  
mahendran@bg-enhance:~/catkin\_ws/src/sweep-ros/launch$