

This is a runtime error prompt

```

/image_raw:=/camera/color/im
age_raw __name:=ORB_SLAM3_mo
no1 __log:=/root/.ros/log/d7
742164-9e72-11ee-863b-0242ac
110005/ORB_SLAM3_mono1-1.log
].
log file: /root/.ros/log/d77
42164-9e72-11ee-863b-0242ac1
10005/ORB_SLAM3_mono1-1*.log
all processes on machine hav
e died, roslaunch will exit
shutting down processing mon
itor...
... shutting down processing
monitor complete
done
root@815ead3bf121:/home/zzk/
o Docker/covins ws#

16394.572447 Duration: 26
.555715 / 275.390517
[RUNNING] Bag Time: 17020
16394.572470 Duration: 26
.555738 / 275.390517
[RUNNING] Bag Time: 17020
16394.581065 Duration: 26
.564334 / 275.390517
[RUNNING] Bag Time: 17020
16394.588470 Duration: 26
.571738 / 275.390517
[RUNNING] Bag Time: 17020
16394.588755 Duration: 26
.572023 / 275.390517

^C
root@815ead3bf121:/home/zzk
o /Dataset/my#
```

This is the content of the launch file :

```

<?xml version='1.0' ?|
<launch|
<arg name='ag_n' default='1' /|
<arg name='voc' default=' (find
covins_comm)/../orb_slam3/Vocabulary/ORBvoc.txt' /|
<arg name='cam' default=' (find
covins_comm)/../orb_slam3/Examples/Monocular/Mono_ugv_zzk.yaml' /|
<node pkg='ORB_SLAM3' type='Mono' name='ORB_SLAM3_monoi (arg ag_n)'
args=' (arg voc) (arg cam)' output='screen' |
<remap from='/camera/image_raw' to='/camera/color/image_raw' /|
```

```
</node|
```

```
</launch|
```

This is the content of the configuration file :

```
%YAML:1.0
```

```
#-----
```

```
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```

```
# Camera Parameters. Adjust them!
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```
#-----
```

```
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```

```
Camera.type: 'PinHole'
```

```
# Camera calibration and distortion parameters (OpenCV)
```

```
Camera.fx: 616.5256737097483
```

```
Camera.fy: 614.2737833318839
```

```
Camera.cx: 320.6623096191914
```

```
Camera.cy: 238.14500131287267
```

```
Camera.k1: 0.1447743999036075
Camera.k2: -0.33013564518115346
Camera.p1: 0.00143314614103631
Camera.p2: -0.0028527506337560913
Camera.k3: 0.0
```

```
Camera.width: 640
Camera.height: 480
```

```
# Camera frames per second
Camera.fps: 30.0
```

```
# Color order of the images (0: BGR, 1: RGB. It is ignored if images are
grayscale)
Camera.RGB: 1
```

```
#-----
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# ORB Parameters
#-----
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```

```
# ORB Extractor: Number of features per image
ORBextractor.nFeatures: 800
```

```
# ORB Extractor: Scale factor between levels in the scale pyramid
ORBextractor.scaleFactor: 1.2
```

```
# ORB Extractor: Number of levels in the scale pyramid
ORBextractor.nLevels: 8
```

```
# ORB Extractor: Fast threshold
# Image is divided in a grid. At each cell FAST are extracted imposing a
minimum response.
# Firstly we impose iniThFAST. If no corners are detected we impose a
lower value minThFAST
# You can lower these values if your images have low contrast
ORBextractor.iniThFAST: 9
ORBextractor.minThFAST: 5
```

```
#-----
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# Viewer Parameters
#-----
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Viewer.KeyFrameSize: 0.05
Viewer.KeyFrameLineWidth: 1
Viewer.GraphLineWidth: 0.9
Viewer.PointSize: 2
```

Viewer.CameraSize: 0.08

Viewer.CameraLineWidth: 3

Viewer.ViewpointX: 0

Viewer.ViewpointY: -0.7

Viewer.ViewpointZ: -1.8

Viewer.ViewpointF: 500