

오류 원본

```
327 ros2 launch turtlebot3_navigation2 navigation2.launch.py map:=$HOME/map.yaml
328 history
329 export TURTLEBOT3_MODEL=burger
330 ros2 rviz rviz
331 history
user@user-X510UAR:~$ !329
export TURTLEBOT3_MODEL=burger
user@user-X510UAR:~$ !327
ros2 launch turtlebot3_navigation2 navigation2.launch.py map:=$HOME/map.yaml
[INFO] [launch]: All log files can be found below /home/user/.ros/log/2023-08-17-16-35-28-090421-user-X510UAR-8949
[INFO] [launch]: Default logging verbosity is set to INFO
[INFO] [component_container_isolated-1]: process started with pid [8963]
[INFO] [rviz2-2]: process started with pid [8965]
```

[rviz2-2] Warning: Ignoring XDG_SESSION_TYPE=wayland on Gnome. Use QT_QPA_PLATFORM=wayland to run on Wayland anyway.

```
[component_container_isolated-1] [INFO] [1692257729.794006754] [nav2_container]:
Load Library: /opt/ros/humble/lib/libmap_server_core.so
[component_container_isolated-1] [INFO] [1692257729.804897494] [nav2_container]:
Found class:
rclcpp_components::NodeFactoryTemplate<nav2_map_server::CostmapFilterInfoServer>

[component_container_isolated-1] [INFO] [1692257729.804947472] [nav2_container]:
Found class: rclcpp_components::NodeFactoryTemplate<nav2_map_server::MapSaver>
[component_container_isolated-1] [INFO] [1692257729.804955898] [nav2_container]:
Found class:
rclcpp_components::NodeFactoryTemplate<nav2_map_server::MapServer>
[component_container_isolated-1] [INFO] [1692257729.804961739] [nav2_container]:
Instantiate class:
rclcpp_components::NodeFactoryTemplate<nav2_map_server::MapServer>
[component_container_isolated-1] [INFO] [1692257729.813082876] [map_server]:
[component_container_isolated-1] map_server lifecycle node launched.
```

[component_container_isolated-1] Waiting on external lifecycle transitions to activate

[component_container_isolated-1] See https://design.ros2.org/articles/node_lifecycle.html for more information.

[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/map_server' in container '/nav2_container'

[component_container_isolated-1] [INFO] [1692257729.813142857] [map_server]: Creating

[component_container_isolated-1] [INFO] [1692257729.816413270] [nav2_container]: Load Library: /opt/ros/humble/lib/libamcl_core.so

[component_container_isolated-1] [INFO] [1692257729.819266610] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_amcl::AmclNode>

[component_container_isolated-1] [INFO] [1692257729.819294311] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_amcl::AmclNode>

[component_container_isolated-1] [INFO] [1692257729.848019537] [amcl]:

[component_container_isolated-1] amcl lifecycle node launched.

[component_container_isolated-1] Waiting on external lifecycle transitions to activate

[component_container_isolated-1] See https://design.ros2.org/articles/node_lifecycle.html for more information.

[component_container_isolated-1] [INFO] [1692257729.848391830] [amcl]: Creating

[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/amcl' in container '/nav2_container'

[component_container_isolated-1] [INFO] [1692257729.864522131] [nav2_container]: Load Library: /opt/ros/humble/lib/libnav2_lifecycle_manager_core.so

[component_container_isolated-1] [INFO] [1692257729.865141692] [nav2_container]: Found class:

rclcpp_components::NodeFactoryTemplate<nav2_lifecycle_manager::LifecycleManager>

[component_container_isolated-1] [INFO] [1692257729.865162730] [nav2_container]: Instantiate class:

rclcpp_components::NodeFactoryTemplate<nav2_lifecycle_manager::LifecycleManager>

[component_container_isolated-1] [INFO] [1692257729.888439956] [lifecycle_manager_localization]: Creating

[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/lifecycle_manager_localization' in container '/nav2_container'

[component_container_isolated-1] [INFO] [1692257729.940751006] [lifecycle_manager_localization]: Creating and initializing lifecycle service clients

[component_container_isolated-1] [INFO] [1692257729.940836277] [nav2_container]: Load Library: /opt/ros/humble/lib/libcontroller_server_core.so

[component_container_isolated-1] [INFO] [1692257729.944127899] [nav2_container]: Found class:

rclcpp_components::NodeFactoryTemplate<nav2_controller::ControllerServer>

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[component_container_isolated-1] [INFO] [1692257729.944163809] [nav2_container]:
Instantiate class:
rclcpp_components::NodeFactoryTemplate<nav2_controller::ControllerServer>
[component_container_isolated-1] [INFO] [1692257729.964009850]
[lifecycle_manager_localization]: Starting managed nodes bringup...
[component_container_isolated-1] [INFO] [1692257729.964062863]
[lifecycle_manager_localization]: Configuring map_server
[component_container_isolated-1] [INFO] [1692257729.964250889] [map_server]:
Configuring
[component_container_isolated-1] [INFO] [map_io]: Loading yaml file:
/home/user/map.yaml
```

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[component_container_isolated-1] [DEBUG] [map_io]: resolution: 0.05
[component_container_isolated-1] [DEBUG] [map_io]: origin[0]: -1.27
[component_container_isolated-1] [DEBUG] [map_io]: origin[1]: -2.25
[component_container_isolated-1] [DEBUG] [map_io]: origin[2]: 0
[component_container_isolated-1] [DEBUG] [map_io]: free_thresh: 0.25
[component_container_isolated-1] [DEBUG] [map_io]: occupied_thresh: 0.65
[component_container_isolated-1] [DEBUG] [map_io]: mode: trinary
[component_container_isolated-1] [DEBUG] [map_io]: negate: 0
[component_container_isolated-1] [INFO] [map_io]: Loading image file:
/home/user/map.pgm
[component_container_isolated-1] [DEBUG] [map_io]: Read map
/home/user/map.pgm: 76 X 88
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```
map @ 0.05 m/cell
[component_container_isolated-1] [INFO] [1692257729.996404007]
[lifecycle_manager_localization]: Configuring amcl
[component_container_isolated-1] [INFO] [1692257729.996531267] [amcl]: Configuring
[component_container_isolated-1] [INFO] [1692257729.996631998] [amcl]:
initTransforms
[rviz2-2] [INFO] [1692257730.031364496] [rviz2]: Stereo is NOT SUPPORTED
[rviz2-2] [INFO] [1692257730.031597319] [rviz2]: OpenGL version: 4.6 (GLSL 4.6)
[rviz2-2] [INFO] [1692257730.052997308] [rviz2]: Stereo is NOT SUPPORTED
[component_container_isolated-1] [INFO] [1692257730.077003389] [controller_server]:
[component_container_isolated-1] controller_server lifecycle node launched.
[component_container_isolated-1] Waiting on external lifecycle transitions to activate
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[component_container_isolated-1] See https://design.ros2.org/articles/node_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692257730.081296829] [controller_server]:
Creating controller server
[component_container_isolated-1] [INFO] [1692257730.127587807] [amcl]: initPubSub

[component_container_isolated-1] [INFO] [1692257730.170687153] [amcl]:
Subscribed to map topic.
[component_container_isolated-1] [ERROR] [1692257730.207452256] []: Caught
exception in callback for transition 10
[component_container_isolated-1] [ERROR] [1692257730.207475541] []: Original
error: According to the loaded plugin descriptions the class differential with base
class type nav2_amcl::MotionModel does not exist. Declared types are
nav2_amcl::DifferentialMotionModel nav2_amcl::OmniMotionModel
[component_container_isolated-1] [WARN] [1692257730.207497168] []: Error
occurred while doing error handling.
[component_container_isolated-1] [FATAL] [1692257730.207508033] [amcl]:
Lifecycle node amcl does not have error state implemented
[component_container_isolated-1] [WARN] [1692257730.207645067] [amcl]: New
subscription discovered on topic '/particle_cloud', requesting incompatible QoS.
No messages will be sent to it. Last incompatible policy:
RELIABILITY_QOS_POLICY
[component_container_isolated-1] [ERROR] [1692257730.207820477]
[lifecycle_manager_localization]: Failed to change state for node: amcl
[component_container_isolated-1] [ERROR] [1692257730.207845639]
[lifecycle_manager_localization]: Failed to bring up all requested nodes. Aborting
bringup.

[component_container_isolated-1] [INFO] [1692257730.259426816]
[local_costmap.local_costmap]:
[component_container_isolated-1] local_costmap lifecycle node launched.
[component_container_isolated-1] Waiting on external lifecycle transitions to activate
[component_container_isolated-1] See https://design.ros2.org/articles/node_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692257730.260401378]
[local_costmap.local_costmap]: Creating Costmap
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/controller_server' in

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container '/nav2_container'
[component_container_isolated-1] [INFO] [1692257730.330267060] [nav2_container]:
Load Library: /opt/ros/humble/lib/libsmoother_server_core.so
[component_container_isolated-1] [INFO] [1692257730.334954368] [nav2_container]:
Found class:
rclcpp_components::NodeFactoryTemplate<nav2_smoother::SmootherServer>
[component_container_isolated-1] [INFO] [1692257730.335046118] [nav2_container]:
Instantiate class:
rclcpp_components::NodeFactoryTemplate<nav2_smoother::SmootherServer>
[component_container_isolated-1] [INFO] [1692257730.490412285] [smoother_server]:
[component_container_isolated-1] smoother_server lifecycle node launched.
[component_container_isolated-1] Waiting on external lifecycle transitions to activate
[component_container_isolated-1] See
https://design.ros2.org/articles/node\_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692257730.496002680] [smoother_server]:
Creating smoother server
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/smoother_server' in
container '/nav2_container'
[component_container_isolated-1] [INFO] [1692257730.502205183] [nav2_container]:
Load Library: /opt/ros/humble/lib/libplanner_server_core.so
[component_container_isolated-1] [INFO] [1692257730.504633531] [nav2_container]:
Found class: rclcpp_components::NodeFactoryTemplate<nav2_planner::PlannerServer>
[component_container_isolated-1] [INFO] [1692257730.504708707] [nav2_container]:
Instantiate class:
rclcpp_components::NodeFactoryTemplate<nav2_planner::PlannerServer>

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[rviz2-2] [WARN] [1692257730.629549545] [rcl.logging_rosout]: Publisher already registered for provided node name. If this is due to multiple nodes with the same name then all logs for that logger name will go out over the existing publisher. As soon as any node with that name is destructed it will unregister the publisher, preventing any further logs for that name from being published on the rosout topic.

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[component_container_isolated-1] [INFO] [1692257730.744121293] [planner_server]:
[component_container_isolated-1] planner_server lifecycle node launched.
[component_container_isolated-1] Waiting on external lifecycle transitions to activate
[component_container_isolated-1] See

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https://design.ros2.org/articles/node_lifecycle.html for more information.

[component_container_isolated-1] [INFO] [1692257730.749647092] [planner_server]:

Creating

[component_container_isolated-1] [INFO] [1692257731.017833330]

[global_costmap.global_costmap]:

[component_container_isolated-1] global_costmap lifecycle node launched.

[component_container_isolated-1] Waiting on external lifecycle transitions to activate

[component_container_isolated-1] See

https://design.ros2.org/articles/node_lifecycle.html for more information.

[component_container_isolated-1] [INFO] [1692257731.018494656]

[global_costmap.global_costmap]: Creating Costmap

[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/planner_server' in container '/nav2_container'

[component_container_isolated-1] [INFO] [1692257731.023879342] [nav2_container]:

Load Library: /opt/ros/humble/lib/libbehavior_server_core.so

[component_container_isolated-1] [INFO] [1692257731.027441679] [nav2_container]:

Found class:

rcldcpp_components::NodeFactoryTemplate<behavior_server::BehaviorServer>

[component_container_isolated-1] [INFO] [1692257731.027509079] [nav2_container]:

Instantiate class:

rcldcpp_components::NodeFactoryTemplate<behavior_server::BehaviorServer>

[component_container_isolated-1] [INFO] [1692257731.160771819] [behavior_server]:

[component_container_isolated-1] behavior_server lifecycle node launched.

[component_container_isolated-1] Waiting on external lifecycle transitions to activate

[component_container_isolated-1] See

https://design.ros2.org/articles/node_lifecycle.html for more information.

[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/behavior_server' in container '/nav2_container'

[component_container_isolated-1] [INFO] [1692257731.173671507] [nav2_container]:

Load Library: /opt/ros/humble/lib/libbt_navigator_core.so

[component_container_isolated-1] [INFO] [1692257731.177657239] [nav2_container]:

Found class:

rcldcpp_components::NodeFactoryTemplate<nav2_bt_navigator::BtNavigator>

[component_container_isolated-1] [INFO] [1692257731.177722103] [nav2_container]:

Instantiate class:

rcldcpp_components::NodeFactoryTemplate<nav2_bt_navigator::BtNavigator>

[component_container_isolated-1] [INFO] [1692257731.283006311] [bt_navigator]:

[component_container_isolated-1] bt_navigator lifecycle node launched.

[component_container_isolated-1] Waiting on external lifecycle transitions to activate

[component_container_isolated-1] See

https://design.ros2.org/articles/node_lifecycle.html for more information.

[component_container_isolated-1] [INFO] [1692257731.283074917] [bt_navigator]:

Creating

[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/bt_navigator' in container '/nav2_container'

[component_container_isolated-1] [INFO] [1692257731.325794349] [nav2_container]:

Load Library: /opt/ros/humble/lib/libwaypoint_follower_core.so

[component_container_isolated-1] [INFO] [1692257731.327446306] [nav2_container]:

Found class:

rclcpp_components::NodeFactoryTemplate<nav2_waypoint_follower::WaypointFollower>

[component_container_isolated-1] [INFO] [1692257731.327517242] [nav2_container]:

Instantiate class:

rclcpp_components::NodeFactoryTemplate<nav2_waypoint_follower::WaypointFollower>

[component_container_isolated-1] [INFO] [1692257731.494136685] [waypoint_follower]:

[component_container_isolated-1] waypoint_follower lifecycle node launched.

[component_container_isolated-1] Waiting on external lifecycle transitions to activate

[component_container_isolated-1] See

https://design.ros2.org/articles/node_lifecycle.html for more information.

[component_container_isolated-1] [INFO] [1692257731.496164214] [waypoint_follower]:

Creating

[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/waypoint_follower' in container '/nav2_container'

[component_container_isolated-1] [INFO] [1692257731.504752962] [nav2_container]:

Load Library: /opt/ros/humble/lib/libvelocity_smoother_core.so

[component_container_isolated-1] [INFO] [1692257731.508555994] [nav2_container]:

Found class:

rclcpp_components::NodeFactoryTemplate<nav2_velocity_smoother::VelocitySmoother>

[component_container_isolated-1] [INFO] [1692257731.508724661] [nav2_container]:

Instantiate class:

rclcpp_components::NodeFactoryTemplate<nav2_velocity_smoother::VelocitySmoother>

[component_container_isolated-1] [INFO] [1692257731.676208137] [velocity_smoother]:

[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/velocity_smoother' in container '/nav2_container'

[component_container_isolated-1] velocity_smoother lifecycle node launched.

[component_container_isolated-1] Waiting on external lifecycle transitions to activate

[component_container_isolated-1] See

https://design.ros2.org/articles/node_lifecycle.html for more information.

[component_container_isolated-1] [INFO] [1692257731.683204717] [nav2_container]:

Found class:

rclcpp_components::NodeFactoryTemplate<nav2_lifecycle_manager::LifecycleManager>

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[component_container_isolated-1] [INFO] [1692257731.683303264] [nav2_container]:
Instantiate class:
rclcpp_components::NodeFactoryTemplate<nav2_lifecycle_manager::LifecycleManager>
[component_container_isolated-1] [INFO] [1692257731.830334702]
[lifecycle_manager_navigation]: Creating
[component_container_isolated-1] [INFO] [1692257731.876199066]
[lifecycle_manager_navigation]: Creating and initializing lifecycle service clients
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node
'/lifecycle_manager_navigation' in container '/nav2_container'
[component_container_isolated-1] [INFO] [1692257732.048378227]
[lifecycle_manager_navigation]: Starting managed nodes bringup...
[component_container_isolated-1] [INFO] [1692257732.048565875]
[lifecycle_manager_navigation]: Configuring controller_server
[component_container_isolated-1] [INFO] [1692257732.049277267] [controller_server]:
Configuring controller interface
[component_container_isolated-1] [INFO] [1692257732.050357938] [controller_server]:
getting goal checker plugins..
[component_container_isolated-1] [INFO] [1692257732.051122376] [controller_server]:
Controller frequency set to 10.0000Hz
[component_container_isolated-1] [INFO] [1692257732.051257894]
[local_costmap.local_costmap]: Configuring
[component_container_isolated-1] [INFO] [1692257732.158012935]
[local_costmap.local_costmap]: Using plugin "obstacle_layer"
[component_container_isolated-1] [INFO] [1692257732.174057131]
[local_costmap.local_costmap]: Subscribed to Topics: scan
[component_container_isolated-1] [INFO] [1692257732.193708380]
[local_costmap.local_costmap]: Initialized plugin "obstacle_layer"
[component_container_isolated-1] [INFO] [1692257732.193784046]
[local_costmap.local_costmap]: Using plugin "voxel_layer"
[component_container_isolated-1] [INFO] [1692257732.195675430]
[local_costmap.local_costmap]: Subscribed to Topics: scan
[component_container_isolated-1] [INFO] [1692257732.276572403]
[local_costmap.local_costmap]: Initialized plugin "voxel_layer"
[component_container_isolated-1] [INFO] [1692257732.276644062]
[local_costmap.local_costmap]: Using plugin "inflation_layer"
[component_container_isolated-1] [INFO] [1692257732.280876941]
[local_costmap.local_costmap]: Initialized plugin "inflation_layer"
[component_container_isolated-1] [INFO] [1692257732.373981969] [controller_server]:
Created progress_checker : progress_checker of type
nav2_controller::SimpleProgressChecker

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[component_container_isolated-1] [INFO] [1692257732.378185486] [controller_server]:
Created goal checker : general_goal_checker of type
nav2_controller::SimpleGoalChecker
[component_container_isolated-1] [INFO] [1692257732.380397814] [controller_server]:
Controller Server has general_goal_checker goal checkers available.
[component_container_isolated-1] [INFO] [1692257732.385883363] [controller_server]:
Created controller : FollowPath of type dwb_core::DWBLocalPlanner
[component_container_isolated-1] [INFO] [1692257732.393002960] [controller_server]:
Setting transform_tolerance to 0.200000
[component_container_isolated-1] [INFO] [1692257732.578850132] [controller_server]:
Using critic "RotateToGoal" (dwb_critics::RotateToGoalCritic)
[component_container_isolated-1] [INFO] [1692257732.582468205] [controller_server]:
Critic plugin initialized
[component_container_isolated-1] [INFO] [1692257732.583072233] [controller_server]:
Using critic "Oscillation" (dwb_critics::OscillationCritic)
[component_container_isolated-1] [INFO] [1692257732.585615087] [controller_server]:
Critic plugin initialized
[component_container_isolated-1] [INFO] [1692257732.586337523] [controller_server]:
Using critic "BaseObstacle" (dwb_critics::BaseObstacleCritic)
[component_container_isolated-1] [INFO] [1692257732.587131055] [controller_server]:
Critic plugin initialized
[component_container_isolated-1] [INFO] [1692257732.587588698] [controller_server]:
Using critic "GoalAlign" (dwb_critics::GoalAlignCritic)
[component_container_isolated-1] [INFO] [1692257732.588852181] [controller_server]:
Critic plugin initialized
[rviz2-2] [INFO] [1692257732.589147630] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257730.589 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257732.589341860] [controller_server]:
Using critic "PathAlign" (dwb_critics::PathAlignCritic)
[component_container_isolated-1] [INFO] [1692257732.590831638] [controller_server]:
Critic plugin initialized
[component_container_isolated-1] [INFO] [1692257732.591498734] [controller_server]:
Using critic "PathDist" (dwb_critics::PathDistCritic)
[component_container_isolated-1] [INFO] [1692257732.592381359] [controller_server]:
Critic plugin initialized
[component_container_isolated-1] [INFO] [1692257732.592779835] [controller_server]:
Using critic "GoalDist" (dwb_critics::GoalDistCritic)
[component_container_isolated-1] [INFO] [1692257732.593653553] [controller_server]:
Critic plugin initialized

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[component_container_isolated-1] [INFO] [1692257732.593711992] [controller_server]:
Controller Server has FollowPath controllers available.

[component_container_isolated-1] [INFO] [1692257732.662716035]
[lifecycle_manager_navigation]: Configuring smoother_server

[component_container_isolated-1] [INFO] [1692257732.663016631] [smoother_server]:
Configuring smoother server

[component_container_isolated-1] [INFO] [1692257732.772416700] [smoother_server]:
Created smoother : simple_smoother of type nav2_smoother::SimpleSmoother

[component_container_isolated-1] [INFO] [1692257732.773676816] [smoother_server]:
Smoother Server has simple_smoother smoothers available.

[rviz2-2] [INFO] [1692257732.812657447] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257730.790 for reason 'discarding message because the
queue is full'

[component_container_isolated-1] [INFO] [1692257732.840589737]
[lifecycle_manager_navigation]: Configuring planner_server

[component_container_isolated-1] [INFO] [1692257732.840842863] [planner_server]:
Configuring

[component_container_isolated-1] [INFO] [1692257732.840889521]
[global_costmap.global_costmap]: Configuring

[component_container_isolated-1] [INFO] [1692257732.882528600]
[global_costmap.global_costmap]: Using plugin "static_layer"

[component_container_isolated-1] [INFO] [1692257732.887812417]
[global_costmap.global_costmap]: Subscribing to the map topic (/map) with transient
local durability

[component_container_isolated-1] [INFO] [1692257732.901715765]
[global_costmap.global_costmap]: Initialized plugin "static_layer"

[component_container_isolated-1] [INFO] [1692257732.901815711]
[global_costmap.global_costmap]: Using plugin "obstacle_layer"

[component_container_isolated-1] [INFO] [1692257732.905424629]
[global_costmap.global_costmap]: Subscribed to Topics: scan

[component_container_isolated-1] [INFO] [1692257732.953671622]
[global_costmap.global_costmap]: Initialized plugin "obstacle_layer"

[component_container_isolated-1] [INFO] [1692257732.953740775]
[global_costmap.global_costmap]: Using plugin "voxel_layer"

[component_container_isolated-1] [INFO] [1692257732.956343892]
[global_costmap.global_costmap]: Subscribed to Topics: scan

[component_container_isolated-1] [INFO] [1692257733.006316571]
[global_costmap.global_costmap]: Initialized plugin "voxel_layer"

[component_container_isolated-1] [INFO] [1692257733.006381492]
[global_costmap.global_costmap]: Using plugin "inflation_layer"

[component_container_isolated-1] [INFO] [1692257733.009614663]
[global_costmap.global_costmap]: Initialized plugin "inflation_layer"
[rviz2-2] [INFO] [1692257733.036732235] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257730.990 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257733.145424737] [planner_server]:
Created global planner plugin GridBased of type nav2_navfn_planner/NavfnPlanner
[component_container_isolated-1] [INFO] [1692257733.145563452] [planner_server]:
Configuring plugin GridBased of type NavfnPlanner
[component_container_isolated-1] [INFO] [1692257733.149622008] [planner_server]:
Planner Server has GridBased planners available.
[rviz2-2] [INFO] [1692257733.229115317] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257731.191 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257733.263332378]
[lifecycle_manager_navigation]: Configuring behavior_server
[component_container_isolated-1] [INFO] [1692257733.263620469] [behavior_server]:
Configuring
[component_container_isolated-1] [INFO] [1692257733.338619184] [behavior_server]:
Creating behavior plugin spin of type nav2_behaviors/Spin
[component_container_isolated-1] [INFO] [1692257733.340507234] [behavior_server]:
Configuring spin
[rviz2-2] [INFO] [1692257733.421310658] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257731.392 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257733.430994052] [behavior_server]:
Creating behavior plugin backup of type nav2_behaviors/BackUp
[component_container_isolated-1] [INFO] [1692257733.433284707] [behavior_server]:
Configuring backup
[component_container_isolated-1] [INFO] [1692257733.536250271] [behavior_server]:
Creating behavior plugin drive_on_heading of type nav2_behaviors/DriveOnHeading
[component_container_isolated-1] [INFO] [1692257733.538825353] [behavior_server]:
Configuring drive_on_heading
[rviz2-2] [INFO] [1692257733.612958437] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257731.592 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257733.635703705] [behavior_server]:
Creating behavior plugin wait of type nav2_behaviors/Wait
[component_container_isolated-1] [INFO] [1692257733.637771095] [behavior_server]:
Configuring wait

[component_container_isolated-1] [INFO] [1692257733.780876573]
[lifecycle_manager_navigation]: Configuring bt_navigator
[component_container_isolated-1] [INFO] [1692257733.781456967] [bt_navigator]:
Configuring
[rviz2-2] [INFO] [1692257733.837050964] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257731.793 for reason 'discarding message because the
queue is full'
[rviz2-2] [INFO] [1692257734.028620744] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257731.994 for reason 'discarding message because the
queue is full'
[rviz2-2] [INFO] [1692257734.221148574] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257732.195 for reason 'discarding message because the
queue is full'
[rviz2-2] [INFO] [1692257734.444976401] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257732.395 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257734.555199863]
[lifecycle_manager_navigation]: Configuring waypoint_follower
[component_container_isolated-1] [INFO] [1692257734.555819672] [waypoint_follower]:
Configuring
[rviz2-2] [INFO] [1692257734.604870487] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257732.596 for reason 'discarding message because the
queue is full'
[rviz2-2] [INFO] [1692257734.828886094] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257732.797 for reason 'discarding message because the
queue is full'
[rviz2-2] [INFO] [1692257735.021012628] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257732.997 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257735.071265317] [waypoint_follower]:
Created waypoint_task_executor : wait_at_waypoint of type
nav2_waypoint_follower::WaitAtWaypoint
[rviz2-2] [INFO] [1692257735.213305019] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257733.198 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257735.240386323]
[lifecycle_manager_navigation]: Configuring velocity_smoother
[component_container_isolated-1] [INFO] [1692257735.241110311] [velocity_smoother]:
Configuring velocity smoother
[component_container_isolated-1] [INFO] [1692257735.258466216]

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[lifecycle_manager_navigation]: Activating controller_server
[component_container_isolated-1] [INFO] [1692257735.259004331] [controller_server]:
Activating
[component_container_isolated-1] [INFO] [1692257735.259079693]
[local_costmap.local_costmap]: Activating
[component_container_isolated-1] [INFO] [1692257735.259112985]
[local_costmap.local_costmap]: Checking transform
[component_container_isolated-1] [INFO] [1692257735.259399245]
[local_costmap.local_costmap]: start
[rviz2-2] [INFO] [1692257735.405643523] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257733.399 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257735.485778496] [controller_server]:
Creating bond (controller_server) to lifecycle manager.
[component_container_isolated-1] [INFO] [1692257735.601121735]
[lifecycle_manager_navigation]: Server controller_server connected with bond.
[component_container_isolated-1] [INFO] [1692257735.601287963]
[lifecycle_manager_navigation]: Activating smoother_server
[component_container_isolated-1] [INFO] [1692257735.602105469] [smoother_server]:
Activating
[component_container_isolated-1] [INFO] [1692257735.602220283] [smoother_server]:
Creating bond (smoother_server) to lifecycle manager.
[rviz2-2] [INFO] [1692257735.661596845] [rviz2]: Message Filter dropping message:
frame 'base_scan' at time 1692257733.599 for reason 'discarding message because the
queue is full'
[component_container_isolated-1] [INFO] [1692257735.716834804]
[lifecycle_manager_navigation]: Server smoother_server connected with bond.
[component_container_isolated-1] [INFO] [1692257735.716957124]
[lifecycle_manager_navigation]: Activating planner_server
[component_container_isolated-1] [INFO] [1692257735.717583724] [planner_server]:
Activating
[component_container_isolated-1] [INFO] [1692257735.717705825]
[global_costmap.global_costmap]: Activating
[component_container_isolated-1] [INFO] [1692257735.717744051]
[global_costmap.global_costmap]: Checking transform
[component_container_isolated-1] [INFO] [1692257735.717788231]
[global_costmap.global_costmap]: Timed out waiting for transform from base_link to map
to become available, tf error: Invalid frame ID "map" passed to canTransform argument
target_frame - frame does not exist
[rviz2-2] [INFO] [1692257735.821190716] [rviz2]: Message Filter dropping message:

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frame 'base_scan' at time 1692257733.800 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257736.013342008] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257734.001 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257736.205877170] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257734.202 for reason 'discarding message because the queue is full'

[component_container_isolated-1] [INFO] [1692257736.217934052]

[global_costmap.global_costmap]: Timed out waiting for transform from base_link to map to become available, tf error: Invalid frame ID "map" passed to canTransform argument target_frame - frame does not exist

[rviz2-2] [INFO] [1692257736.429575801] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257734.403 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257736.621856428] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257734.603 for reason 'discarding message because the queue is full'

[component_container_isolated-1] [INFO] [1692257736.717936759]

[global_costmap.global_costmap]: Timed out waiting for transform from base_link to map to become available, tf error: Invalid frame ID "map" passed to canTransform argument target_frame - frame does not exist

[rviz2-2] [INFO] [1692257736.813519679] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257734.803 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257737.005438057] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257735.004 for reason 'discarding message because the queue is full'

[component_container_isolated-1] [INFO] [1692257737.218054508]

[global_costmap.global_costmap]: Timed out waiting for transform from base_link to map to become available, tf error: Invalid frame ID "map" passed to canTransform argument target_frame - frame does not exist

[rviz2-2] [INFO] [1692257737.228772174] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257735.205 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257737.421530957] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257735.406 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257737.485406027] [rviz2]: Message Filter dropping message: frame 'odom' at time 1692257735.423 for reason 'discarding message because the

queue is full'

[rviz2-2] [INFO] [1692257737.613488300] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257735.606 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257737.677749574] [rviz2]: Message Filter dropping message: frame 'odom' at time 1692257735.623 for reason 'discarding message because the queue is full'

[component_container_isolated-1] [INFO] [1692257737.717930942]
[global_costmap.global_costmap]: Timed out waiting for transform from base_link to map to become available, tf error: Invalid frame ID "map" passed to canTransform argument target_frame - frame does not exist

[rviz2-2] [INFO] [1692257737.805365331] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257735.807 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257737.869874591] [rviz2]: Message Filter dropping message: frame 'odom' at time 1692257735.823 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257738.029625746] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257736.007 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257738.093256837] [rviz2]: Message Filter dropping message: frame 'odom' at time 1692257736.023 for reason 'discarding message because the queue is full'

[component_container_isolated-1] [INFO] [1692257738.217892486]
[global_costmap.global_costmap]: Timed out waiting for transform from base_link to map to become available, tf error: Invalid frame ID "map" passed to canTransform argument target_frame - frame does not exist

[rviz2-2] [INFO] [1692257738.221239494] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257736.208 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257738.285634703] [rviz2]: Message Filter dropping message: frame 'odom' at time 1692257736.223 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257738.413727357] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692257736.409 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257738.477812406] [rviz2]: Message Filter dropping message: frame 'odom' at time 1692257736.423 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257738.604999364] [rviz2]: Message Filter dropping message:

frame 'base_scan' at time 1692257736.609 for reason 'discarding message because the queue is full'

[rviz2-2] [INFO] [1692257738.669311716] [rviz2]: Message Filter dropping message:

frame 'odom' at time 1692257736.623 for reason 'discarding message because the queue is full'

[component_container_isolated-1] [INFO] [1692257738.717893535]

[global_costmap.global_costmap]: Timed out waiting for transform from base_link to map to become available, tf error: Invalid frame ID "map" passed to canTransform argument target_frame - frame does not exist

```
user@user-X510UAR: $ !
ros2 launch turtlebot3_navigation2 navigation2.launch.py map:=SHOME/map.yaml
[INFO] [launch]: All log files can be found below /home/user/.ros/log/2023-08-17-23-14-52-961798-user-X510UAR-36630
[INFO] [launch]: Default logging verbosity is set to INFO
[INFO] [component_container_isolated-1]: process started with pid [36644]
[INFO] [rviz2-2]: process started with pid [36646]
[rviz2-2] Warning: Ignoring XDG_SESSION_TYPE=wayland on Gnome. Use QT_QPA_PLATFORM=wayland to run on Wayland anyway.
[component_container_isolated-1] [INFO] [1692281694.68482945] [nav2_container]: Load Library: /opt/ros/humble/lib/libnav_server_core.so
[component_container_isolated-1] [INFO] [1692281694.697272799] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_map_server::CostmapFilterInfoServer>
[component_container_isolated-1] [INFO] [1692281694.697333145] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_map_server::MapSaver>
[component_container_isolated-1] [INFO] [1692281694.697346718] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_map_server::MapServer>
[component_container_isolated-1] [INFO] [1692281694.697372495] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_map_server::MapServer>
[component_container_isolated-1] [INFO] [1692281694.884488987] [map_server]:
[component_container_isolated-1] map_server lifecycle node launched.
[component_container_isolated-1] Waiting on external lifecycle transitions to activate
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/map_server' in container '/nav2_container'
[component_container_isolated-1] See https://design.ros2.org/articles/node_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692281694.884536125] [map_server]: Creating
[component_container_isolated-1] [INFO] [1692281694.884939290] [nav2_container]: Load Library: /opt/ros/humble/lib/libcontroller_server_core.so
[component_container_isolated-1] [INFO] [1692281694.889665926] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_controller::ControllerServer>
[component_container_isolated-1] [INFO] [1692281694.889761708] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_controller::ControllerServer>
[rviz2-2] [INFO] [1692281694.891151927] [rviz2]: Stereo is NOT SUPPORTED
[rviz2-2] [INFO] [1692281694.891978931] [rviz2]: OpenCL version: 4.0 (GLSL 4.0)
[rviz2-2] [INFO] [1692281694.914064379] [rviz2]: Stereo is NOT SUPPORTED
[component_container_isolated-1] [INFO] [1692281696.698340660] [controller_server]:
[component_container_isolated-1] controller_server lifecycle node launched.
[component_container_isolated-1] Waiting on external lifecycle transitions to activate
[component_container_isolated-1] See https://design.ros2.org/articles/node_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692281696.712456958] [controller_server]: Creating controller server
[component_container_isolated-1] [INFO] [1692281698.230113293] [local_costmap.local_costmap]:
[component_container_isolated-1] local_costmap lifecycle node launched.
[component_container_isolated-1] Waiting on external lifecycle transitions to activate
[component_container_isolated-1] See https://design.ros2.org/articles/node_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692281699.231855574] [local_costmap.local_costmap]: Creating
[component_container_isolated-1] [INFO] [1692281699.584987055] [nav2_container]: Load Library: /opt/ros/humble/lib/libancl_core.so
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/controller_server' in container '/nav2_container'
[component_container_isolated-1] [INFO] [1692281699.589961126] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_ancl::AnclNode>
[component_container_isolated-1] [INFO] [1692281699.510885598] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_ancl::AnclNode>
[rviz2-2] [WARN] [1692281705.134472338] [rcl_logging_rosout]: Publisher already registered for provided node name. If this is due to multiple nodes with the same name then all logs for that logger name w
ll go out over the existing publisher.
As soon as any node with that name is destructed it will unregister the publisher, preventing any further logs for that name from being published on the rosout top
ic.
[component_container_isolated-1] [INFO] [1692281705.237716684] [ancl]:
[component_container_isolated-1] ancl lifecycle node launched.
[component_container_isolated-1] Waiting on external lifecycle transitions to activate
[component_container_isolated-1] See https://design.ros2.org/articles/node_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692281705.238691106] [ancl]: Creating
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/ancl' in container '/nav2_container'
[component_container_isolated-1] [INFO] [1692281705.978700079] [nav2_container]: Load Library: /opt/ros/humble/lib/libsmoother_server_core.so
[component_container_isolated-1] [INFO] [1692281705.984494987] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_smoother::SmootherServer>
[component_container_isolated-1] [INFO] [1692281705.984507493] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_smoother::SmootherServer>
[component_container_isolated-1] [INFO] [1692281709.101719270] [smoother_server]:
[component_container_isolated-1] smoother_server lifecycle node launched.
[component_container_isolated-1] Waiting on external lifecycle transitions to activate
[component_container_isolated-1] See https://design.ros2.org/articles/node_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692281709.105773800] [smoother_server]: Creating smoother server
[component_container_isolated-1] [INFO] [1692281709.106916058] [nav2_container]: Load Library: /opt/ros/humble/lib/libnav2_lifecycle_manager_core.so
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/smoother_server' in container '/nav2_container'
[component_container_isolated-1] [INFO] [1692281709.108058064] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_lifecycle_manager::LifecycleManager>
[component_container_isolated-1] [INFO] [1692281709.108136013] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_lifecycle_manager::LifecycleManager>
[rviz2-2] [INFO] [1692281710.629085498] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281708.003 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281710.629044668] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281708.204 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281710.412917780] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281708.405 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281710.637375688] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281708.605 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281710.829268451] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281708.806 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281711.621580171] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281709.007 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281711.245275798] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281709.208 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281711.437195495] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281709.409 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281711.629480183] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281709.609 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281711.821455472] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281709.811 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281711.911238021] [lifecycle_manager.localization]: Creating
[rviz2-2] [INFO] [1692281712.045387715] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281710.011 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281712.115190640] [lifecycle_manager.localization]: Creating and initializing lifecycle manager clients
[component_container_isolated-1] [INFO] [1692281712.115277806] [nav2_container]: Load Library: /opt/ros/humble/lib/libplanner_server_core.so
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/lifecycle_manager.localization' in container '/nav2_container'
[component_container_isolated-1] [INFO] [1692281712.116923531] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_planner::PlannerServer>
[component_container_isolated-1] [INFO] [1692281712.116968074] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_planner::PlannerServer>
[rviz2-2] [INFO] [1692281712.236883358] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281710.212 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281712.429637537] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281710.413 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281712.653425616] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281710.614 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281712.836979081] [lifecycle_manager.localization]: Creating map server
[component_container_isolated-1] [INFO] [1692281712.839856422] [lifecycle_manager.localization]: Configuring map server
[component_container_isolated-1] [INFO] [1692281712.840513351] [map_server]: Configuring
[component_container_isolated-1] [INFO] [map_io]: Loading yaml file: /home/user/map.yaml
[component_container_isolated-1] [DEBUG] [map_io]: resolution: 0.05
[component_container_isolated-1] [DEBUG] [map_io]: origin[0]: -1.27
[component_container_isolated-1] [DEBUG] [map_io]: origin[1]: -2.25
[component_container_isolated-1] [DEBUG] [map_io]: origin[2]: 0
[component_container_isolated-1] [DEBUG] [map_io]: Free thresh: 0.25
[component_container_isolated-1] [DEBUG] [map_io]: occupied_thresh: 0.65
[component_container_isolated-1] [DEBUG] [map_io]: mode: trinary
[component_container_isolated-1] [DEBUG] [map_io]: negate: 0
[component_container_isolated-1] [INFO] [map_io]: Loading image file: /home/user/map.pgm
[rviz2-2] [INFO] [1692281712.845269709] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281710.815 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [DEBUG] [map_io]: Read map /home/user/map.pgm: 70 x 88 map @ 0.05 m/cell
[rviz2-2] [INFO] [1692281713.637938594] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281711.015 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281713.228607176] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281711.216 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281713.453802504] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281711.417 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281713.645544218] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281711.617 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281713.837578466] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281711.818 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281714.028938635] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281712.018 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281714.253069869] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281712.218 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281714.445204436] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281712.419 for reason 'discarding message because the queue is full'
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[component_container_isolated-1] [INFO] [1692281714.456355439] [lifecycle_manager.localization]: Configuring ancl
[component_container_isolated-1] [INFO] [1692281714.456828384] [ancl]: Configuring
[component_container_isolated-1] [INFO] [1692281714.457212484] [ancl]: initTransforms
[rviz2-2] [INFO] [1692281714.460466819] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281712.620 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281714.828974388] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281712.820 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281715.053163359] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281713.021 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281715.245323807] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281713.222 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281715.437233884] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281713.422 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281715.661164603] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281713.623 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281715.852889657] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281713.823 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281716.044666819] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281714.023 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281716.237027537] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281714.224 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281716.331911013] [ancl]: initPubSub
[rviz2-2] [INFO] [1692281716.468784944] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281714.425 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281716.483328848] [planner_server]: Creating
[component_container_isolated-1] [INFO] [1692281716.49049662] [ancl]: Subscribed to map topic.
[rviz2-2] [INFO] [1692281716.653288877] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281714.625 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [ERROR] [1692281716.758612631] [1]: Caught exception in callback for transition 10
[component_container_isolated-1] [ERROR] [1692281716.758698708] [1]: Original error: According to the loaded plugin descriptions the class differential with base class type nav2_ancl::MotionModel does not exist. Declared types are nav2_ancl::DifferentialMotionModel nav2_ancl::OmniMotionModel
[component_container_isolated-1] [WARN] [1692281716.758834488] [1]: Error occurred while doing error handling.
[component_container_isolated-1] [FATAL] [1692281716.758977442] [ancl]: lifecycle node ancl does not have error state implemented
[component_container_isolated-1] [ERROR] [1692281716.759795757] [lifecycle_manager.localization]: Failed to change state for node: ancl
[component_container_isolated-1] [ERROR] [1692281716.759898063] [lifecycle_manager.localization]: Failed to bring up all requested nodes. Aborting bringup.
[rviz2-2] [INFO] [1692281716.844347473] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281714.826 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281717.037589338] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281715.027 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281717.09526832] [global_costmap.global_costmap]:
[component_container_isolated-1] [INFO] [1692281717.09526832] [global_costmap.global_costmap]: global_costmap lifecycle node launched.
[component_container_isolated-1] [INFO] [1692281717.09526832] [global_costmap.global_costmap]: Waiting on external lifecycle transitions to activate
[component_container_isolated-1] [INFO] [1692281717.09526832] [global_costmap.global_costmap]: See https://design.ros2.org/articles/node_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692281717.101098031] [global_costmap.global_costmap]: Creating Costmap
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/planner_server' in container '/nav2_container'
[component_container_isolated-1] [INFO] [1692281717.207143419] [nav2_container]: Load Library: /opt/ros/humble/lib/libbehavior_server_core.so
[component_container_isolated-1] [INFO] [1692281717.207143419] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<behavior_server::BehaviorServer>
[component_container_isolated-1] [INFO] [1692281717.207231799] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<behavior_server::BehaviorServer>
[rviz2-2] [INFO] [1692281717.261284329] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281715.227 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281717.453197959] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281715.427 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281717.645178924] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281715.628 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281717.785730157] [behavior_server]:
[component_container_isolated-1] [INFO] [1692281717.785730157] [behavior_server]: behavior_server lifecycle node launched.
[component_container_isolated-1] [INFO] [1692281717.785730157] [behavior_server]: Waiting on external lifecycle transitions to activate
[component_container_isolated-1] [INFO] [1692281717.785730157] [behavior_server]: See https://design.ros2.org/articles/node_lifecycle.html for more information.
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/behavior_server' in container '/nav2_container'
[component_container_isolated-1] [INFO] [1692281717.802693859] [nav2_container]: Load Library: /opt/ros/humble/lib/libbt_navigator_core.so
[component_container_isolated-1] [INFO] [1692281717.802693859] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_bt_navigator::BTNavigator>
[component_container_isolated-1] [INFO] [1692281717.80358976] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_bt_navigator::BTNavigator>
[rviz2-2] [INFO] [1692281717.868674918] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281715.829 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281718.092857223] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281716.029 for reason 'discarding message because the queue is full'

[component_container_isolated-1] [INFO] [1692281718.461599068] [nav2_container]: Load Library: /opt/ros/humble/lib/libwaypoint_follower_core.so
[component_container_isolated-1] [INFO] [1692281718.463619557] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_waypoint_follower::WaypointFollower>
[component_container_isolated-1] [INFO] [1692281718.463619557] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_waypoint_follower::WaypointFollower>
[rviz2-2] [INFO] [1692281718.474903883] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281716.431 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281718.668885426] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281716.632 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281718.868678163] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281716.833 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281719.052862576] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281717.033 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281719.277064252] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281717.234 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281719.469354552] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281717.435 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281719.573764844] [waypoint_follower]:
[component_container_isolated-1] [INFO] [1692281719.573764844] [waypoint_follower]: waypoint_follower lifecycle node launched.
[component_container_isolated-1] [INFO] [1692281719.573764844] [waypoint_follower]: Waiting on external lifecycle transitions to activate
[component_container_isolated-1] [INFO] [1692281719.573764844] [waypoint_follower]: See https://design.ros2.org/articles/node_lifecycle.html for more information.
[component_container_isolated-1] [INFO] [1692281719.574923270] [waypoint_follower]: Creating
[rviz2-2] [INFO] [1692281719.661315859] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281717.635 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281719.852818932] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281717.836 for reason 'discarding message because the queue is full'
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/waypoint_follower' in container '/nav2_container'
[component_container_isolated-1] [INFO] [1692281719.952765507] [nav2_container]: Load Library: /opt/ros/humble/lib/libvelocity_smoother_core.so
[component_container_isolated-1] [INFO] [1692281719.954062703] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_velocity_smoother::VelocitySmoother>
[component_container_isolated-1] [INFO] [1692281719.954137114] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_velocity_smoother::VelocitySmoother>
[rviz2-2] [INFO] [1692281720.076973165] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281718.037 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281720.281455968] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281718.237 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281720.461520234] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281718.438 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281720.652948694] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281718.638 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281720.838083338] [velocity_smoother]:
[component_container_isolated-1] [INFO] [1692281720.838083338] [velocity_smoother]: velocity_smoother lifecycle node launched.
[component_container_isolated-1] [INFO] [1692281720.838083338] [velocity_smoother]: Waiting on external lifecycle transitions to activate
[component_container_isolated-1] [INFO] [1692281720.838083338] [velocity_smoother]: See https://design.ros2.org/articles/node_lifecycle.html for more information.
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/velocity_smoother' in container '/nav2_container'
[component_container_isolated-1] [INFO] [1692281720.837515443] [nav2_container]: Found class: rclcpp_components::NodeFactoryTemplate<nav2_lifecycle_manager::LifecycleManager>
[component_container_isolated-1] [INFO] [1692281720.837622738] [nav2_container]: Instantiate class: rclcpp_components::NodeFactoryTemplate<nav2_lifecycle_manager::LifecycleManager>
[rviz2-2] [INFO] [1692281720.877124578] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281718.838 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281721.069443285] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281719.039 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281721.261794528] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281719.240 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281721.432430187] [lifecycle_manager.navigation]: Creating
[rviz2-2] [INFO] [1692281721.485506159] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281719.440 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281721.530289552] [lifecycle_manager.navigation]:
[INFO] [launch_ros.actions.load_composable_nodes]: Loaded node '/lifecycle_manager.navigation' in container '/nav2_container'
[rviz2-2] [INFO] [1692281721.677788776] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281719.641 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281721.868967932] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281719.842 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281722.061568531] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281720.042 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281722.285971856] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281720.243 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281722.477470005] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281720.444 for reason 'discarding message because the queue is full'
[rviz2-2] [INFO] [1692281722.669360952] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281720.644 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281723.044924466] [lifecycle_manager.navigation]: Starting managed nodes bringup.
[component_container_isolated-1] [INFO] [1692281723.044938259] [lifecycle_manager.navigation]: Configuring controller_server
[component_container_isolated-1] [INFO] [1692281723.045203072] [controller_server]: Configuring controller interface
[component_container_isolated-1] [INFO] [1692281723.045617519] [controller_server]: getting goal checker plugins.
[component_container_isolated-1] [INFO] [1692281723.045839286] [controller_server]: Controller frequency set to 10.0000Hz
[component_container_isolated-1] [INFO] [1692281723.045988266] [local_costmap.local_costmap]: Configuring
[rviz2-2] [INFO] [1692281723.080684812] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281723.046 for reason 'discarding message because the queue is full'

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[component_container_isolated-1] [INFO] [1692281724.033895559] [local_costmap.local_costmap]: Subscribed to /robot_scan
[rvt22-2] [INFO] [1692281724.077398957] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281722.048 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281724.268608283] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281722.249 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281724.460974499] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281722.450 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281724.6048081572] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281722.650 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281724.685504820] [local_costmap.local_costmap]: Initialized plugin "voxel_layer"
[component_container_isolated-1] [INFO] [1692281724.685619989] [local_costmap.local_costmap]: Using plugin "inflation_layer"
[component_container_isolated-1] [INFO] [1692281724.691081370] [local_costmap.local_costmap]: Initialized plugin "inflation_layer"
[rvt22-2] [INFO] [1692281724.877202615] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281722.851 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281725.069284900] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281723.051 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281725.261451600] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281723.252 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281725.485199730] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281723.453 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281725.5487291151] [controller_server]: Created progress_checker : progress_checker of type nav2_controller::SimpleProgressChecker
[component_container_isolated-1] [INFO] [1692281725.551904045] [controller_server]: Created goal_checker : general_goal_checker of type nav2_controller::SimpleGoalChecker
[component_container_isolated-1] [INFO] [1692281725.554418599] [controller_server]: Controller Server has general_goal_checker goal checkers available.
[rvt22-2] [INFO] [1692281725.677771357] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281723.653 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281725.741670490] [controller_server]: Setting transform_tolerance to 0.200000
[rvt22-2] [INFO] [1692281725.809122108] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281723.854 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281726.093372858] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281724.055 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281726.285340962] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281724.257 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281726.442263180] [controller_server]: Using critic "RotateToGoal" (dwb_critics::RotateToGoalCritic)
[component_container_isolated-1] [INFO] [1692281726.446279873] [controller_server]: Critic plugin initialized
[component_container_isolated-1] [INFO] [1692281726.447164073] [controller_server]: Using critic "Oscillation" (dwb_critics::OscillationCritic)
[component_container_isolated-1] [INFO] [1692281726.452373019] [controller_server]: Critic plugin initialized
[component_container_isolated-1] [INFO] [1692281726.453168932] [controller_server]: Using critic "BaseObstacle" (dwb_critics::BaseObstacleCritic)
[component_container_isolated-1] [INFO] [1692281726.454409152] [controller_server]: Critic plugin initialized
[component_container_isolated-1] [INFO] [1692281726.455009707] [controller_server]: Using critic "GoalAlign" (dwb_critics::GoalAlignCritic)
[rvt22-2] [INFO] [1692281726.476554169] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281724.456 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281726.597980407] [controller_server]: Critic plugin initialized
[component_container_isolated-1] [INFO] [1692281726.599310263] [controller_server]: Using critic "PathAlign" (dwb_critics::PathAlignCritic)
[component_container_isolated-1] [INFO] [1692281726.602338394] [controller_server]: Critic plugin initialized
[component_container_isolated-1] [INFO] [1692281726.603450138] [controller_server]: Using critic "PathDist" (dwb_critics::PathDistCritic)
[component_container_isolated-1] [INFO] [1692281726.606027740] [controller_server]: Critic plugin initialized
[component_container_isolated-1] [INFO] [1692281726.607099931] [controller_server]: Using critic "GoalDist" (dwb_critics::GoalDistCritic)
[component_container_isolated-1] [INFO] [1692281726.609228970] [controller_server]: Critic plugin initialized
[component_container_isolated-1] [INFO] [1692281726.609348025] [controller_server]: Controller Server has FollowPath controllers available.
[rvt22-2] [INFO] [1692281726.700941402] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281724.657 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281726.924901723] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281724.857 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281726.990871121] [lifecycle_manager.navigation]: Configuring smother\_server
[component_container_isolated-1] [INFO] [1692281726.991142131] [smoother_server]: Configuring smoother server
[rvt22-2] [INFO] [1692281727.085247297] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281725.059 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281727.300351692] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281725.260 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281727.467297510] [smoother_server]: Created smoother : simple_smoother of type nav2_smoother::SimpleSmoother
[component_container_isolated-1] [INFO] [1692281727.469035059] [smoother_server]: Smoother Server has simple_smoother smoothers available.
[rvt22-2] [INFO] [1692281727.532592303] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281725.460 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281727.692850749] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281725.661 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281727.885219679] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281725.862 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281728.077459102] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281726.062 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281728.301501461] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281726.263 for reason 'discarding message because the queue is full'
[rvt22-2] [INFO] [1692281728.493321845] [rviz2]: Message Filter dropping message: frame 'base_scan' at time 1692281726.464 for reason 'discarding message because the queue is full'
[component_container_isolated-1] [INFO] [1692281728.63100533] [lifecycle_manager.navigation]: Configuring planner\_server
[component_container_isolated-1] [INFO] [1692281728.631021311] [planner_server.configuration]
```