状态码64位无符号整型：每一位0表示正常，1表示不正常

从低到高64位：

|  |  |  |  |
| --- | --- | --- | --- |
| 位数 | topic | 所在节点 | 备注 |
| 0 | /sirius/sensor/ins/imu | /ins\_driver | 组合惯导 |
| 1 | /sirius/sensor/ins/global\_pose | /ins\_driver |
| 2 | /sirius/sensor/ins/motion\_status | /ins\_driver |
|  | | | |
| 3 | /sirius/chasis/chasis\_status | /wolf\_chasis\_driver |  |
|  | | | |
| 4 | /left\_rfans16/rfans\_driver/rfans\_packets | /left\_rfans16/rfans\_driver | left\_rfans\_lidar |
| 5 | /left\_rfans16/rfans\_driver/rfans\_points | /left\_rfans16/calculation\_node |
| 6 | /right\_rfans16/rfans\_driver/rfans\_packets | /right\_rfans16/rfans\_driver | right\_rfans\_lidar |
| 7 | /right\_rfans16/rfans\_driver/rfans\_points | /right\_rfans16/calculation\_node |
| 8 | /sirius/sensor/lidar/LRmerged\_lidar\_points\_preprocessed | /multi\_lidar\_preprocess | multi\_lidar |
| 9 | /sirius/sensor/lidar/center\_lidar\_points\_preprocessed | /pandar40p | pandar40p\_lidar |
|  | | | |
| 10 | /sirius/sensor/camera/image\_left | /mvs\_image\_left\_pub | left\_mvs\_camera |
| 11 | /sirius/sensor/camera/image\_right | /mvs\_image\_right\_pub | right\_mvs\_camera |
|  | | | |
| 12 | /zed\_node/left/image\_rect\_color | left\_zed | zed\_camera |
| 13 | /zed\_node/right/image\_rect\_color | right\_zed |
|  | | | |
| 14 | /sirius/hmi/remote\_control | /udp2ros | udp2ros |
| 15 | /sirius/hmi/guide\_trajectory | /udp2ros |
| 16 | /sirius/hmi/xxx | /udp2ros |
|  | | | |
| 17 | /sirius/ccob/guide\_point\_l | /ccob | ccob |
| 18 | /sirius/ccob/guide\_trajectory\_l | /ccob |
| 19 | /sirius/ccob/udc | /ccob |
| 20 | /sirius/ccob/remote\_control | /ccob |
|  | | | |
| 21 | /sirius/planning/guide\_trajectory\_l | /astar\_avoid |  |
|  | | | |
| 22 | /sirius/control/chasis\_motion\_command | /control |  |
|  | | | |
| 23 | /sirius/localization/local\_pose | /local\_pose | local\_pose |
|  |  |  |  |
| 24 | /sirius/perception/occupancy\_grid | /costmap\_generator | perception |
| 25 | /sirius/perception/lidar/points\_no\_ground | /ground\_segmentation |
|  | | | |
| 26 | /filtered\_points | lidar\_mapping | lidar\_SLAM |
| 27 | /odom |
| 28 | /sirius/localization/estimate\_pose | lidar\_localization |
|  |  |  |  |
| 29 | /tf | tf |  |
| 30 |  |  |  |
|  |  |  |  |