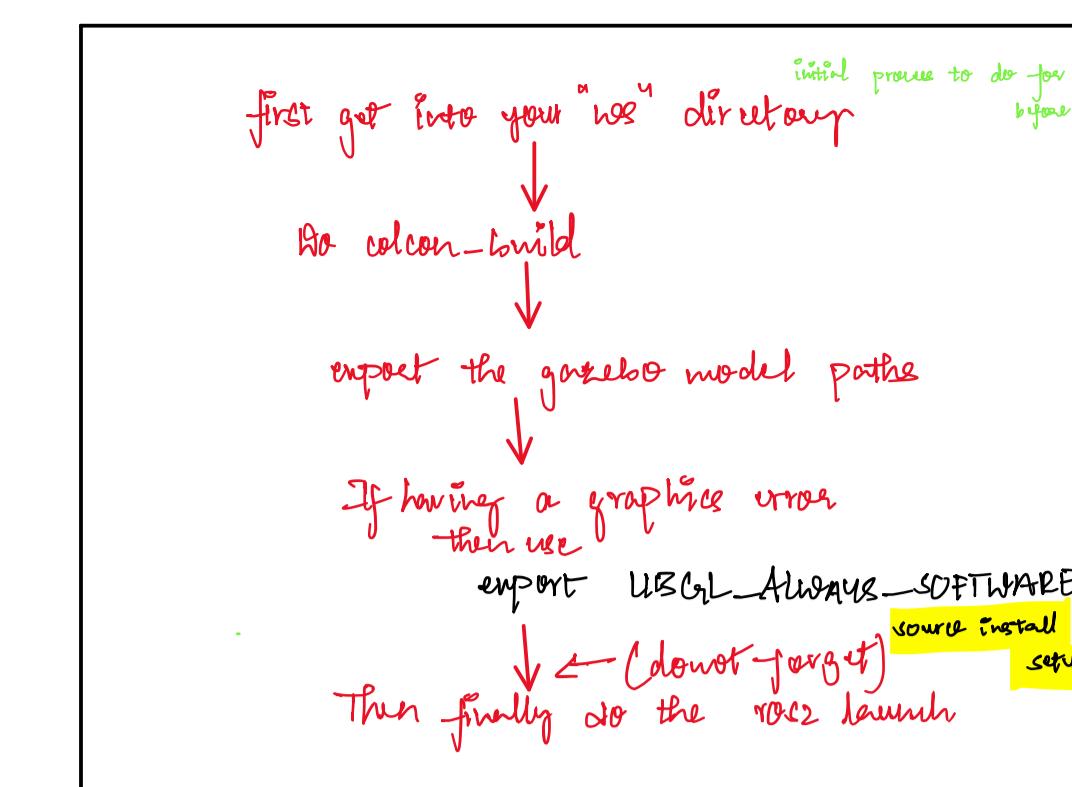
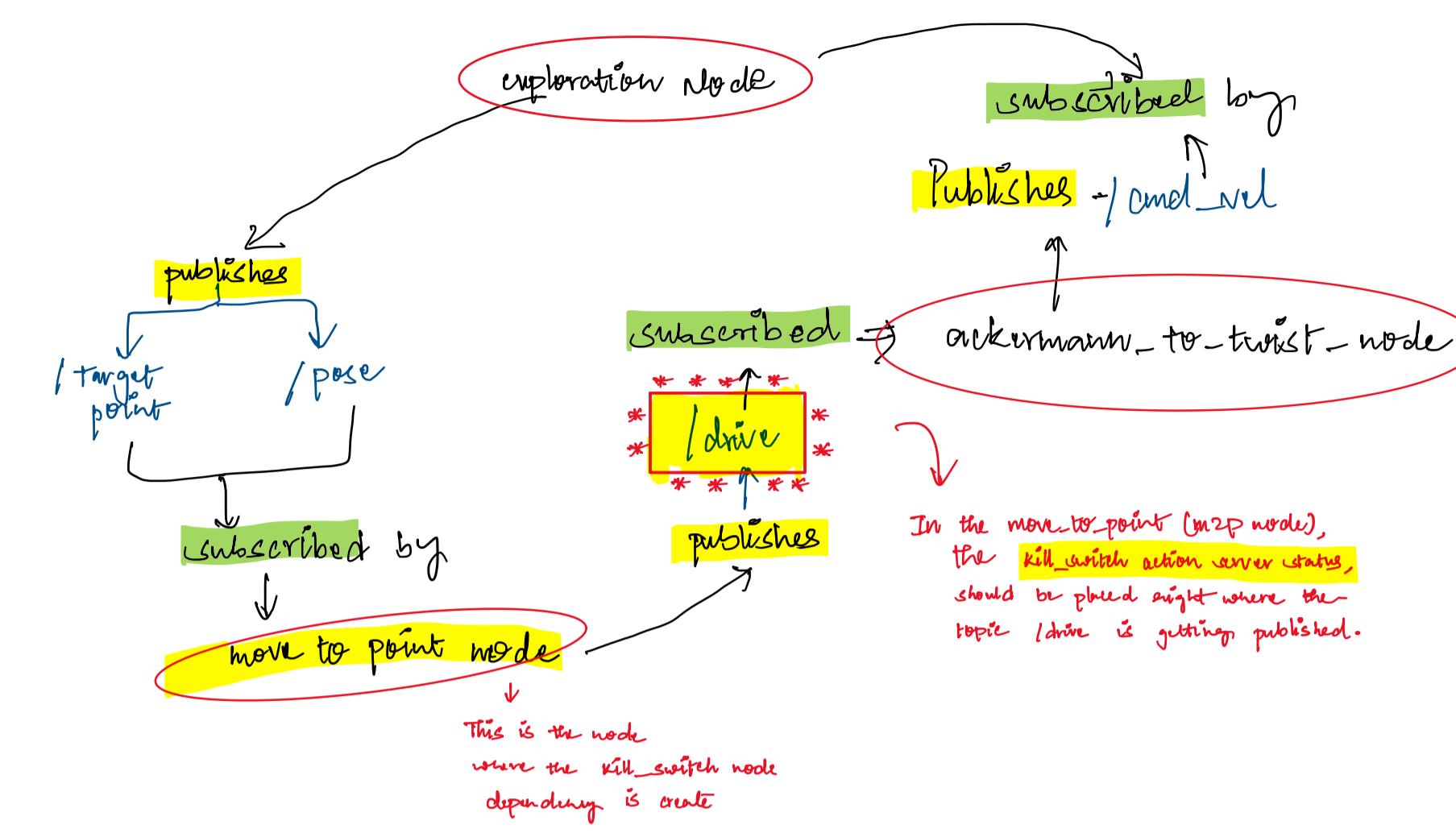
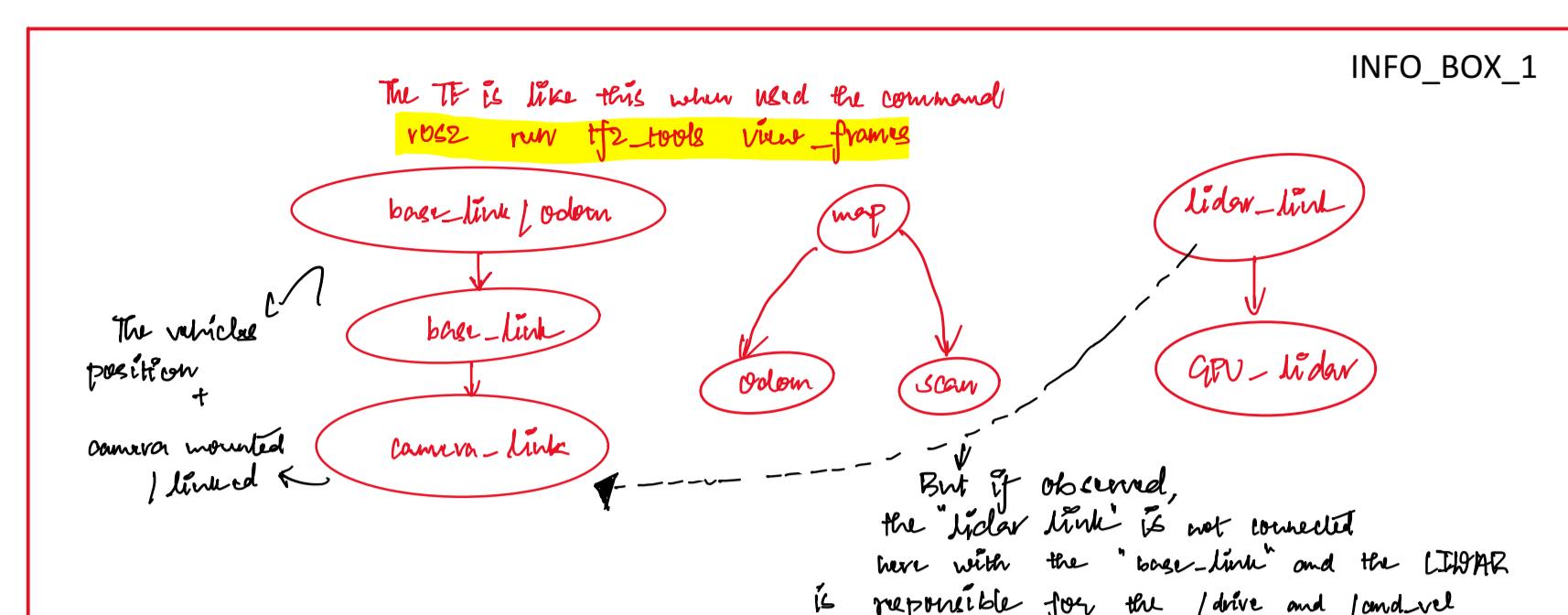


ROS2 kill switch implementation



+ Step 3



→ the laser data (both range/camera /meta data) are fine. But still the issue persists with the LIDAR.

Checked with any other possibilities with chart CPT

→ Now as per the explanation given in the info_box, if the `laser-link` is not connected with the `base-link`, this might be key possibility here.

→ May 25/04/2025 1: log on the ROS kill switch implementation.

On the directory `ROS-project`

Still finding the same self file errors:
→ the self files are in a normal order of
model -> world -> scene -> self

1. solved this error
→ make sure to maintain the
same names [for ex: blue-car]
for -> self file
→ inside model - config
→ also the folder name

2. make sure to make the
change in 'car' folder
and then do the colcon build.

Then launch Gazebo

Then import world path & check them

After fixed that errors at 20:35

The user this time was
"XML_PARSING" in the lines
of the model config file
when checked our file
observed that the parser
should be excluded with `</model>`?

Manually edited the model config
file and this time, observed no self
XML_PARSING

[this issue with the self parsing
cause the self error through a
chain reaction]

AFTER THIS
EVEN THE
LAZER-SIM
IS functioning

Solution

- Now the issue even if the Gazebo
GUI is launching successfully,
the car itself gazebo is not moving.
→ Need to do the /topic - publisher
responsibility for the car driving and then
work on it!

node → move-to-point

Publishing → Subscribing

/drive → pose / target point

before publisher node : move-to-point
subscriber node : acknowledgement, information-node

acknowledging → lidar

subscribing → lidar

publishing → lidar

move-to-point → lidar

lidar → feedback

feedback → pose topic

pose topic → move-to-point

move-to-point → lidar

lidar → feedback

feedback → lidar

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