

# tier4\_perception\_launch is giving me error during launching #3808

Unanswered **muratgozum45** asked this question in Q&A



**muratgozum45** on Sep 5, 2023

Hi all,

I was launching the tier4\_perception\_launch with the command:  
`ros2 launch tier4_perception_launch perception.launch.xml`  
In the beginning it was giving me error due to the parameter files with empty paths and I did replace their paths from the tier4\_perception\_component\_launch.xml file. Afterwards, it gave me another error:  
[ERROR] [launch]: Caught exception in launch (see debug for traceback): 'front\_overhang'

I do not know for what reason I am having this error. As far as I know 'front\_overhang' is a parameter for the part that is between front wheel center and vehicle front and in the vehicle\_info.param.yaml file its value is given as 1 (default).  
Did anyone encounter with this error during their launching of perception module? Or does anybody know how to resolve this issue?  
Thanks,  
Murat

↑ 1

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**zillur-av** on Sep 5, 2023

You can not just launch `tier4_perception_launch perception.launch.xml` without providing required `param` files. I encountered this error too. It is because one of the nodes ask for `sample_vehicle_description/config/vehicle_info.param.yaml` like file. But, it's not mentioned anywhere. what you can do: you can launch the main launch file `autoware.launch.xml` and keep other modules `false`. In that way, hopefully you will not encounter this.

↑ 1

2 replies



**muratgozum45** on Sep 5, 2023

Author

Thank you very much [@zillur-av](#) . I did try that but what would be the best way to see the performance of the perception stack? I would like to see the effects of the changes I do for the parameters related to the perception stack. You think launching `autoware.launch.xml` only like this:  
will be sufficient? or is there anything else I have to do?



**zillur-av** on Sep 5, 2023

Yes, it should work. Launch `autoware.launch` and keep other modules like localization, planning, control false so that you can deal with fewer nodes