检查python配置：sudo update-alternative --config python

# SyntaxError: Missing parentheses in call to ‘print‘. Did you mean print(e)?

修改mbot\_teleop.py文件

报错：无法启动节点<robot\_state\_publisher/state\_publisher>

ERROR: cannot launch node of type [robot\_state\_publisher/state\_publisher]: Cannot locate node of type [state\_publisher] in package [robot\_state\_publisher]. Make sure file exists in package path and permission is set to executable (chmod +x)

原因：名称不对应导致无法定位该节点，修改display\_mrobot\_chassis\_urdf.launch文件中robot\_state\_publisher的type:

将

<!-- 运行robot\_state\_publisher节点，发布tf -->

<node name="robot\_state\_publisher" pkg="robot\_state\_publisher" type="state\_publisher" />

1

2

修改为

<!-- 运行robot\_state\_publisher节点，发布tf -->

<node name="robot\_state\_publisher" pkg="robot\_state\_publisher" type="robot\_state\_publisher" />

1

2

在rviz中打开后没有出现joint\_state\_publisher图形控制界面，也就无法来调节控制rviz中对应轮子模型的转动

原因：可能是版本更新的问题，现在joint\_state\_publisher节点不会调出图形控制界面，需要下载joint\_state\_publisher\_gui并修改display\_mrobot\_chassis\_urdf.launch文件。

下载joint\_state\_publisher\_gui

$ sudo apt-get install ros-noetic-joint-state-publisher-gui

1

然后修改display\_mrobot\_chassis\_urdf.launch文件，将joint\_state\_publisher替换为joint\_state\_publisher\_gui

<!-- 运行joint\_state\_publisher节点，发布机器人的关节状态 -->

<node name="joint\_state\_publisher\_gui" pkg="joint\_state\_publisher\_gui" type="joint\_state\_publisher\_gui" />