

```
aero@intelaero:~$ roslaunch local_planner local_planner_aero.launch
... logging to /home/aero/.ros/log/4dd4115a-cbee-11e8-990b-4a4c1c6e760a/roslaunch-intelaero-6184.log
Checking log directory for disk usage. This may take awhile.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.
```

```
started roslaunch server http://intelaero:37410/
```

SUMMARY

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```

CLEAR PARAMETERS

```
* /mavros/
```

PARAMETERS

```
* /camera/camera_nodelet_manager/num_worker_threads: 4
* /camera/depth_rectify_depth/interpolation: 0
* /camera/disparity_depth/max_range: 4.0
* /camera/disparity_depth/min_range: 0.5
* /camera/disparity_registered_sw/max_range: 4.0
* /camera/disparity_registered_sw/min_range: 0.5
* /camera/driver/base_frame_id: camera_link
* /camera/driver/camera_type: R200
* /camera/driver/color_fps: 30
* /camera/driver/color_frame_id: camera_rgb_frame
* /camera/driver/color_height: 480
* /camera/driver/color_optical_frame_id: camera_rgb_optica...
* /camera/driver/color_width: 640
* /camera/driver/depth_fps: 30
* /camera/driver/depth_frame_id: camera_depth_frame
* /camera/driver/depth_height: 360
* /camera/driver/depth_optical_frame_id: camera_depth_opti...
* /camera/driver/depth_width: 480
* /camera/driver/enable_color: True
* /camera/driver/enable_depth: True
* /camera/driver/enable_fisheye: False
* /camera/driver/enable_imu: False
* /camera/driver/enable_ir2: True
* /camera/driver/enable_ir: True
* /camera/driver/enable_pointcloud: False
* /camera/driver/enable_tf: True
* /camera/driver/fisheye_frame_id: camera_fisheye_frame
* /camera/driver/fisheye_optical_frame_id: camera_fisheye_op...
* /camera/driver/imu_frame_id: camera_imu_frame
* /camera/driver/imu_optical_frame_id: camera_imu_optica...
* /camera/driver/ir2_frame_id: camera_ir2_frame
* /camera/driver/ir2_optical_frame_id: camera_ir2_optica...
* /camera/driver/ir_frame_id: camera_ir_frame
* /camera/driver/ir_optical_frame_id: camera_ir_optical...
* /camera/driver/mode: manual
* /camera/driver/serial_no:
* /camera/driver/usb_port_id:
* /camera/points_xyzrgb_sw_registered/queue_size: 100
* /local_planner_node/depth_points_topic: /camera/depth/points
* /local_planner_node/goal_x_param: 15
* /local_planner_node/goal_y_param: 15
* /local_planner_node/goal_z_param: 4
* /mavros/cmd/use_comp_id_system_control: False
* /mavros/conn/heartbeat_rate: 1.0
* /mavros/conn/system_time_rate: 1.0
* /mavros/conn/timeout: 10.0
* /mavros/conn/timesync_rate: 10.0
* /mavros/distance_sensor/hrlv_ez4_pub/field_of_view: 0.0
* /mavros/distance_sensor/hrlv_ez4_pub/frame_id: hrlv_ez4_sonar
* /mavros/distance_sensor/hrlv_ez4_pub/id: 0
* /mavros/distance_sensor/hrlv_ez4_pub/orientation: ROLL_180
* /mavros/distance_sensor/hrlv_ez4_pub/send_tf: True
* /mavros/distance_sensor/hrlv_ez4_pub/sensor_position/x: 0.0
* /mavros/distance_sensor/hrlv_ez4_pub/sensor_position/y: 0.0
* /mavros/distance_sensor/hrlv_ez4_pub/sensor_position/z: -0.1
* /mavros/distance_sensor/laser_1_sub/id: 3
* /mavros/distance_sensor/laser_1_sub/orientation: ROLL_180
* /mavros/distance_sensor/laser_1_sub/subscriber: True
```

```

* /mavros/distance_sensor/lidarlite_pub/field_of_view: 0.0
* /mavros/distance_sensor/lidarlite_pub/frame_id: lidarlite_laser
* /mavros/distance_sensor/lidarlite_pub/id: 1
* /mavros/distance_sensor/lidarlite_pub/orientation: ROLL_180
* /mavros/distance_sensor/lidarlite_pub/send_tf: True
* /mavros/distance_sensor/lidarlite_pub/sensor_position/x: 0.0
* /mavros/distance_sensor/lidarlite_pub/sensor_position/y: 0.0
* /mavros/distance_sensor/lidarlite_pub/sensor_position/z: -0.1
* /mavros/distance_sensor/sonar_1_sub/id: 2
* /mavros/distance_sensor/sonar_1_sub/orientation: ROLL_180
* /mavros/distance_sensor/sonar_1_sub/subscriber: True
* /mavros/fcu_protocol: v2.0
* /mavros/fcu_url: udp://:14540@loca...
* /mavros/gcs_url:
* /mavros/global_position/frame_id: fcu
* /mavros/global_position/rot_covariance: 99999.0
* /mavros/global_position/tf/child_frame_id: fcu_utm
* /mavros/global_position/tf/frame_id: local_origin
* /mavros/global_position/tf/send: False
* /mavros/image/frame_id: px4flow
* /mavros/imu/angular_velocity_stdev: 0.000349065850399
* /mavros/imu/frame_id: fcu
* /mavros/imu/linear_acceleration_stdev: 0.0003
* /mavros/imu/magnetic_stdev: 0.0
* /mavros/imu/orientation_stdev: 1.0
* /mavros/local_position/frame_id: local_origin
* /mavros/local_position/tf/child_frame_id: fcu
* /mavros/local_position/tf/frame_id: local_origin
* /mavros/local_position/tf/send: True
* /mavros/local_position/tf/send_fcu: False
* /mavros/mission/pull_after_gcs: True
* /mavros/mocap/use_pose: False
* /mavros/mocap/use_tf: True
* /mavros/plugin_blacklist: ['safety_area', '...
* /mavros/plugin_whitelist: []
* /mavros/px4flow/frame_id: px4flow
* /mavros/px4flow/ranger_fov: 0.0
* /mavros/px4flow/ranger_max_range: 5.0
* /mavros/px4flow/ranger_min_range: 0.3
* /mavros/safety_area/p1/x: 1.0
* /mavros/safety_area/p1/y: 1.0
* /mavros/safety_area/p1/z: 1.0
* /mavros/safety_area/p2/x: -1.0
* /mavros/safety_area/p2/y: -1.0
* /mavros/safety_area/p2/z: -1.0
* /mavros/setpoint_accel/send_force: False
* /mavros/setpoint_attitude/reverse_throttle: False
* /mavros/setpoint_attitude/tf/child_frame_id: attitude
* /mavros/setpoint_attitude/tf/frame_id: local_origin
* /mavros/setpoint_attitude/tf/listen: False
* /mavros/setpoint_attitude/tf/rate_limit: 10.0
* /mavros/setpoint_position/tf/child_frame_id: setpoint
* /mavros/setpoint_position/tf/frame_id: local_origin
* /mavros/setpoint_position/tf/listen: False
* /mavros/setpoint_position/tf/rate_limit: 50.0
* /mavros/startup_px4_usb_quirk: True
* /mavros/sys/disable_diag: False
* /mavros/sys/min_voltage: 10.0
* /mavros/target_component_id: 1
* /mavros/target_system_id: 1
* /mavros/tdr_radio/low_rssi: 40
* /mavros/time/time_ref_source: fcu
* /mavros/time/timesync_avg_alpha: 0.6
* /mavros/vibration/frame_id: vibration
* /mavros/vision_pose/tf/child_frame_id: vision
* /mavros/vision_pose/tf/frame_id: local_origin
* /mavros/vision_pose/tf/listen: False
* /mavros/vision_pose/tf/rate_limit: 10.0
* /mavros/vision_speed/listen_twist: False
* /roscdistro: kinetic
* /rosversion: 1.12.13
* /use_sim_time: False

```

```
/camera/  
camera_nodelet_manager (nodelet/nodelet)  
depth_metric (nodelet/nodelet)  
depth_metric_rect (nodelet/nodelet)  
depth_points (nodelet/nodelet)  
depth_rectify_depth (nodelet/nodelet)  
depth_registered_sw_metric_rect (nodelet/nodelet)  
disparity_depth (nodelet/nodelet)  
disparity_registered_sw (nodelet/nodelet)  
driver (nodelet/nodelet)  
ir_rectify_ir (nodelet/nodelet)  
points_xyzrgb_sw_registered (nodelet/nodelet)  
register_depth_rgb (nodelet/nodelet)  
rgb_debayer (nodelet/nodelet)  
rgb_rectify_color (nodelet/nodelet)  
rgb_rectify_mono (nodelet/nodelet)  
/  
local_planner_node (local_planner/local_planner_node)  
mavros (mavros/mavros_node)  
tf_90_deg (tf/static_transform_publisher)  
tf_depth_camera (tf/static_transform_publisher)
```

```
auto-starting new master  
process[master]: started with pid [6194]  
ROS_MASTER_URI=http://localhost:11311
```

```
setting /run_id to 4dd4115a-cbee-11e8-990b-4a4c1c6e760a  
process[rosout-1]: started with pid [6207]  
started core service [/rosout]  
process[tf_90_deg-2]: started with pid [6226]  
process[tf_depth_camera-3]: started with pid [6227]  
process[mavros-4]: started with pid [6236]  
process[camera/camera_nodelet_manager-5]: started with pid [6240]  
process[camera/driver-6]: started with pid [6250]  
process[camera/rgb_debayer-7]: started with pid [6253]  
process[camera/rgb_rectify_mono-8]: started with pid [6259]  
process[camera/rgb_rectify_color-9]: started with pid [6261]  
process[camera/ir_rectify_ir-10]: started with pid [6267]  
process[camera/depth_rectify_depth-11]: started with pid [6273]  
process[camera/depth_metric_rect-12]: started with pid [6276]  
process[camera/depth_metric-13]: started with pid [6290]  
process[camera/depth_points-14]: started with pid [6300]  
process[camera/register_depth_rgb-15]: started with pid [6305]  
process[camera/points_xyzrgb_sw_registered-16]: started with pid [6308]  
process[camera/depth_registered_sw_metric_rect-17]: started with pid [6319]  
process[camera/disparity_depth-18]: started with pid [6329]  
process[camera/disparity_registered_sw-19]: started with pid [6333]  
process[local_planner_node-20]: started with pid [6337]  
[ INFO] [1539108503.202233757]: Initializing nodelet with 4 worker threads.  
[ INFO] [1539108503.567020999]: FCU URL: udp://:14540@localhost:14557  
[ INFO] [1539108503.570874798]: udp0: Bind address: 0.0.0.0:14540  
[ INFO] [1539108503.571499178]: udp0: Remote address: 127.0.0.1:14557  
[ INFO] [1539108503.571780972]: GCS bridge disabled  
[ INFO] [1539108503.622749385]: Plugin 3dr_radio loaded  
[ INFO] [1539108503.639598154]: Plugin 3dr_radio initialized  
[ INFO] [1539108503.640202658]: Plugin actuator_control loaded  
[ INFO] [1539108503.669349075]: Plugin actuator_control initialized  
[ INFO] [1539108503.676518625]: Plugin adsb loaded  
[ INFO] [1539108503.709337666]: Plugin adsb initialized  
[ INFO] [1539108503.709977147]: Plugin altitude loaded  
[ INFO] [1539108503.722746515]: Plugin altitude initialized  
[ INFO] [1539108503.723359006]: Plugin cam_imu_sync loaded  
[ INFO] [1539108503.728307868]: Plugin cam_imu_sync initialized  
[ INFO] [1539108503.728918347]: Plugin command loaded  
[ INFO] [1539108503.792114652]: Plugin command initialized  
[ INFO] [1539108503.792720293]: Plugin debug_value loaded  
[ INFO] [1539108503.852910644]: Plugin debug_value initialized  
[ INFO] [1539108503.852997413]: Plugin distance_sensor blacklisted  
[ INFO] [1539108503.853875185]: Plugin fake_gps loaded  
[DEBUG] [1539108503.935615050]: [OA] Dynamic reconfigure call  
[ INFO] [1539108503.955387381]: Plugin fake_gps initialized  
[ INFO] [1539108503.956073152]: Plugin ftp loaded  
[ INFO] [1539108504.005576268]: Plugin ftp initialized  
[ INFO] [1539108504.006329758]: Plugin global_position loaded
```

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Intel RealSense F200_camera ; 2.60.0.0
Intel RealSense LR200_camera ; 2.0.71.18
Intel RealSense R200_camera ; 1.0.72.06
Intel RealSense SR300_camera ; 3.10.10.0
Intel RealSense ZR300_adapter ; 1.29.0.0
Intel RealSense ZR300_camera ; 2.0.71.28
Intel RealSense ZR300_motion_module ; 1.25.0.0
[ INFO] [1539108504.036813373]: /camera/driver - Detected the following camera:
      - Serial No: 2481004490, USB Port ID: 2-4, Name: Intel RealSense R200, Camera
      FW: 1.0.71.06
[ WARN] [1539108504.036895028]: /camera/driver - Detected unvalidated firmware:
      - 2481004490's current camera firmware is 1.0.71.06, Validated camera
firmware is 1.0.72.06
[ INFO] [1539108504.036953682]: /camera/driver - Connecting to camera with Serial No: 2481004490, USB Port ID
: 2-4
[ INFO] [1539108504.188479312]: Plugin global_position initialized
[ INFO] [1539108504.189168084]: Plugin hil loaded
[ INFO] [1539108504.369536780]: Plugin hil initialized
[ INFO] [1539108504.370207889]: Plugin home_position loaded
[ INFO] [1539108504.414165666]: Plugin home_position initialized
[ INFO] [1539108504.414850000]: Plugin imu loaded
[ INFO] [1539108504.512816169]: Plugin imu initialized
[ INFO] [1539108504.513096939]: Plugin local_position loaded
[ INFO] [1539108504.560783647]: ===== Set Goal =====: [15.000000, 15.000000, 4.000000].
[ INFO] [1539108504.587358344]: Plugin local_position initialized
[ INFO] [1539108504.588053830]: Plugin manual_control loaded
[ INFO] [1539108504.616070389]: Plugin manual_control initialized
[ INFO] [1539108504.616744960]: Plugin mocap_pose_estimate loaded
[ INFO] [1539108504.645833030]: Plugin mocap_pose_estimate initialized
[ INFO] [1539108504.646530790]: Plugin obstacle_distance loaded
[ INFO] [1539108504.673371306]: Plugin obstacle_distance initialized
[ INFO] [1539108504.673604960]: Plugin odom loaded
[ INFO] [1539108504.698701631]: Plugin odom initialized
[ INFO] [1539108504.699499386]: Plugin param loaded
[ INFO] [1539108504.721128719]: Plugin param initialized
[ INFO] [1539108504.721789502]: Plugin px4flow loaded
[ INFO] [1539108504.783499997]: Plugin px4flow initialized
[ INFO] [1539108504.783593666]: Plugin rangefinder blacklisted
[ INFO] [1539108504.784233072]: Plugin rc_io loaded
[ INFO] [1539108504.813688930]: Plugin rc_io initialized
[ INFO] [1539108504.813778986]: Plugin safety_area blacklisted
[ INFO] [1539108504.814455632]: Plugin setpoint_accel loaded
[ INFO] [1539108504.840270528]: Plugin setpoint_accel initialized
[ INFO] [1539108504.840991065]: Plugin setpoint_attitude loaded
[ INFO] [1539108504.917583768]: Plugin setpoint_attitude initialized
[ INFO] [1539108504.918322869]: Plugin setpoint_position loaded
[ INFO] [1539108505.032841881]: Plugin setpoint_position initialized
[ INFO] [1539108505.033596383]: Plugin setpoint_raw loaded
[ INFO] [1539108505.112885385]: Plugin setpoint_raw initialized
[ INFO] [1539108505.113621273]: Plugin setpoint_velocity loaded
[ INFO] [1539108505.164122945]: Plugin setpoint_velocity initialized
[ INFO] [1539108505.164597065]: Plugin sys_status loaded
[ INFO] [1539108505.219062248]: /camera/driver - Setting static camera options
[ INFO] [1539108505.229283243]: Plugin sys_status initialized
[ INFO] [1539108505.229715798]: Plugin sys_time loaded
[ INFO] [1539108505.259648420]: /camera/driver - Enabling Depth in manual mode
[ INFO] [1539108505.260304666]: /camera/driver - Enabling Color in manual mode
[ INFO] [1539108505.261058268]: /camera/driver - Enabling IR in manual mode
[ INFO] [1539108505.261405217]: /camera/driver - Enabling IR2 in manual mode
[ INFO] [1539108505.261625820]: /camera/driver - Starting camera
[ INFO] [1539108505.277007447]: TM: Timesync mode: MAVLINK
[ INFO] [1539108505.283312421]: Plugin sys_time initialized
[ INFO] [1539108505.284034334]: Plugin trajectory loaded
[ INFO] [1539108505.292283430]: /camera/driver - Publishing camera transforms (/tf_static)
[ INFO] [1539108505.292707434]: /camera/driver - Setting dynamic camera options (r200_dc_preset=5)
[ INFO] [1539108505.311305722]: Plugin trajectory initialized
[ INFO] [1539108505.311693223]: Plugin vfr_hud loaded
[ INFO] [1539108505.314001033]: Plugin vfr_hud initialized
[ INFO] [1539108505.314376447]: Plugin vibration blacklisted
[ INFO] [1539108505.314604875]: Plugin vision_pose_estimate loaded
[ INFO] [1539108505.349433786]: Plugin vision_pose_estimate initialized
[ INFO] [1539108505.349673665]: Plugin vision_speed_estimate loaded
[ INFO] [1539108505.366030635]: Plugin vision_speed_estimate initialized
[ INFO] [1539108505.366445102]: Plugin waypoint loaded

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[ INFO] [1539108505.385054877]: Plugin waypoint initialized
[ INFO] [1539108505.385343997]: Plugin wind_estimation loaded
[ INFO] [1539108505.387829007]: Plugin wind_estimation initialized
[ INFO] [1539108505.388037109]: Autostarting mavlink via USB on PX4
[ INFO] [1539108505.388128228]: Built-in SIMD instructions: SSE, SSE2
[ INFO] [1539108505.388204145]: Built-in MAVLink package version: 2018.7.18
[ INFO] [1539108505.388254461]: Known MAVLink dialects: common ardupilotmega ASLUAV autoquad icarous
matrixpilot paparazzi slugs standard uAvionix ualberta
[ INFO] [1539108505.388312440]: MAVROS started. MY ID 1.240, TARGET ID 1.1
[ INFO] [1539108505.963747603]: /camera/driver - Initializing Depth Control Preset to 5
[ WARN] [1539108506.561341343]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108506.562039492]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108506.611226291]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108506.611462532]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108506.661225222]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108506.661469926]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108506.711310721]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108506.711570427]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108506.761234996]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108506.761569670]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108506.811226739]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108506.811477394]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108506.861235583]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108506.861564756]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108506.911375449]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108506.911610390]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108506.961216981]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108506.961448922]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108507.011245483]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108507.011522415]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108507.061224181]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108507.061587881]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108507.111502287]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108507.111761468]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108507.161307498]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108507.161979070]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108507.211232292]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108507.211490285]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108507.261219316]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108507.261481547]: Pointcloud timeout: No position received, no WP to output....

[ WARN] [1539108507.311428630]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108507.311713575]: Pointcloud timeout: No position received, no WP to output....

[ INFO] [1539108509.400184734]: /camera/driver - Setting dynamic camera options
Exception in thread Thread-3 (most likely raised during interpreter shutdown):
Traceback (most recent call last):
  File "/usr/lib/python2.7/threading.py", line 801, in __bootstrap_inner
  File "/usr/lib/python2.7/threading.py", line 754, in run
  File "/opt/ros/kinetic/lib/python2.7/dist-packages/rospy/impl/tcpros_base.py", line 154, in run
<type 'exceptions.AttributeError': 'NoneType' object has no attribute 'timeout'
[ERROR] [1539108510.405943176]: Received an exception trying to transform a point from "camera_optical_frame"
to "local_origin": Could not find a connection between 'local_origin' and 'camera_depth_optical_frame'
[ WARN] [1539108510.406359244]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108510.406739934]: Pointcloud timeout: No position received, no WP to output....

[ERROR] [1539108513.424404037]: Received an exception trying to transform a point from "camera_optical_frame"
to "local_origin": Could not find a connection between 'local_origin' and 'camera_depth_optical_frame'
[ WARN] [1539108513.424659081]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108513.425078474]: Pointcloud timeout: No position received, no WP to output....

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[ERROR] [1539108516.450860190]: Received an exception trying to transform a point from "camera_optical_frame"
to "local_origin": Could not find a connection between 'local_origin' and 'camera_depth_optical_frame'
[ WARN] [1539108516.450999738]: MSG to TF: Quaternion Not Properly Normalized
[ WARN] [1539108516.451122197]: Pointcloud timeout: No position received, no WP to output....
```

```
^C[local_planner_node-20] killing on exit
[camera/disparity_registered_sw-19] killing on exit
[camera/disparity_depth-18] killing on exit
[camera/depth_registered_sw_metric_rect-17] killing on exit
[camera/points_xyzrgb_sw_registered-16] killing on exit
[camera/register_depth_rgb-15] killing on exit
[camera/depth_points-14] killing on exit
[camera/depth_metric-13] killing on exit
[camera/depth_rectify_depth-11] killing on exit
[camera/depth_metric_rect-12] killing on exit
[camera/ir_rectify_ir-10] killing on exit
[camera/rgb_rectify_color-9] killing on exit
[camera/rgb_rectify_mono-8] killing on exit
[camera/rgb_debayer-7] killing on exit
[camera/driver-6] killing on exit
[camera/camera_nodelet_manager-5] killing on exit
[mavros-4] killing on exit
[tf_depth_camera-3] killing on exit
[tf_90_deg-2] killing on exit
[local_planner_node-20] escalating to SIGTERM
[rosout-1] killing on exit
[master] killing on exit
shutting down processing monitor...
... shutting down processing monitor complete
done
```