



链滴

[ROS]using roswtf

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原文链接: <https://ld246.com/article/1472524740586>

来源网站: [链滴](#)

许可协议: [署名-相同方式共享 4.0 国际 \(CC BY-SA 4.0\)](#)

<p>本文开始之前先把 roscore 关闭。 </p>

<p>####1.检查安装</p>

<p>roswtf 检查系统并试图检查问题: </p>

```
<pre><code class="highlight-chroma"><span class="highlight-line"><span class="highlight-cl">$ roscd</span></span><span class="highlight-line"><span class="highlight-cl">$ roswtf</span></span></code></pre>
```

<p>可以看到类似的内容: </p>

```
<pre><code class="highlight-chroma"><span class="highlight-line"><span class="highlight-cl">Stack: ros</span></span><span class="highlight-line"><span class="highlight-cl">=====  
=====  
=====
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">Static checks su  
mary:
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">No errors or warn  
ngs
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">=====  
=====  
=====
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">Cannot communi  
cate with master, ignoring graph checks
```

```
</span></span></code></pre>
```

<p>如果安装有问題可以看到类似下面的输出: `` </p>

<p>"Stack: ros": roswtf uses whatever your current directory is to determine what checks it does. This is telling us that you started roswtf in the ros stack.

"Static checks summary": this is a report on any filesystem issues. It's telling us that there were no errors.

"Cannot communicate with master, ignoring graph checks": the roscore isn't running, so roswtf didn't do any online checks.</p>

```
<pre><code class="highlight-chroma"><span class="highlight-line"><span class="highlight-cl">
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">####2.Trying it on  
ine
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">For this next step,  
we want a Master to be up, so go ahead and start a roscore.
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">首先通过roscore  
动Master。运行:
```

```
</span></span></code></pre>
```

```
<p>$ roscd<br>
```

```
$ roswtf</p>
```

```
<pre><code class="highlight-chroma"><span class="highlight-line"><span class="highlight-cl">可以看到类似的输出:
```

```
</span></span></code></pre>
```

```
<h2 id="Stack--ros">Stack: ros</h2>
```

```
<p>Static checks summary:</p>
```

```
<h2 id="No-errors-or-warnings">No errors or warnings</h2>
```

```
<p>Beginning tests of your ROS graph. These may take awhile...<br>  
analyzing graph...<br>
```

```
... done analyzing graph<br>
```

```
running graph rules...<br>
```

```
... done running graph rules</p>
```

Online checks summary:

Found 1 warning(s).

Warnings are things that may be just fine, but are sometimes at fault

WARNING The following node subscriptions are unconnected:

-

- /rosout:

 -

- /rosout

 -

-

 -

```
<code class="highlight-chroma"><span class="highlight-line"><span class="highlight-cl">rosrtf对roscout运行之后的图做了一些在线的检查。根据启动的节点的数量，检查所花费的时间也不同。检查完毕之后可以看大类似的输出:
```

WARNING The following node subscriptions are unconnected:

-

- /rosout:

 -

- /rosout

 -

-

 -

```
<code class="highlight-chroma"><span class="highlight-line"><span class="highlight-cl">rosrtf警告roscout节点需要向一个主题订阅，但是没有有一个节点发布。这种情况，因为我们本来没有运行其他的节点，所以可以忽略这个警告。
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">####2.Errors
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">rosrtf警告有些东是有问题的，但是这可能很正常。rosrtf也可以检查出错误，并可以报告错误。
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">这里我们向ROSPA KAGE_PATH设置一个错误的值。停止之前运行的Master节点让输出看起来简单一点。
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">
```

```
</span></span></code></pre>
```

\$ roscd

```
<span class="language-math"> ROS_PACKAGE_PATH=bad:</span>ROS_PACKAGE_PATH ro  
wtf
```

This time we see:

Stack: ros

Static checks summary:

Found 1 error(s).

ERROR Not all paths in ROS_PACKAGE_PATH [bad] point to an existing directory:

-

- bad

 -

```
<p>=====  
=====
```

Cannot communicate with master, ignoring graph checks

```
<code class="highlight-chroma"><span class="highlight-line"><span class="highlight-cl">
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">正如上面的输出，r  
swtf检查出了ROSPACKAGE_PATH设置的错误。
```

```
</span></span><span class="highlight-line"><span class="highlight-cl">rosrtf可以检查出
```

多其他类型的错误。如果在编码的过程被构建和交流问题难倒，可以使用roswtf来看看能不能给出正的方向。

```
</span> </span> <span class="highlight-line"> <span class="highlight-cl">  
</span> </span> <span class="highlight-line"> <span class="highlight-cl">  
</span> </span> </code> </pre>
```