

The broadcasting-specific cold-joint was not installed



Summary of Content

The missing broadcasting-specific cold-joint could refer either to a ROS2 joint state broadcaster not being properly loaded or to a cold-shrink cable joint not installed, each requiring different corrective actions.

ROS2 Joint State Broadcaster Context

In ROS2, a joint state broadcaster reads all state interfaces of a robot and publishes them on topics like `/joint_states` or `/dynamic_joint_states`. If the broadcaster is not installed or configured correctly, you may see warnings or errors such as missing joints or interfaces parameters. Common causes include:

- The parameter file for the broadcaster is not loaded or incorrectly referenced in the launch file.
- The joints or interfaces parameters are empty, preventing the broadcaster from publishing any joint states.
- The controller node is launched without the necessary `--param-file` argument.

Resolution steps:

- Ensure the parameter file defining the joint state broadcaster is correctly passed to the `ros2_control_node`.
- Verify that the joints and interfaces parameters are properly defined in the YAML configuration.
- Confirm that the launch file references the correct parameter file and that the controller manager is active.

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By default, all available joint state interfaces are used, unless configured otherwise. In the latter case, resulting interfaces is defined

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If any of the combinations of the defined joints parameter and interfaces parameter are not in the available state interfaces, the

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