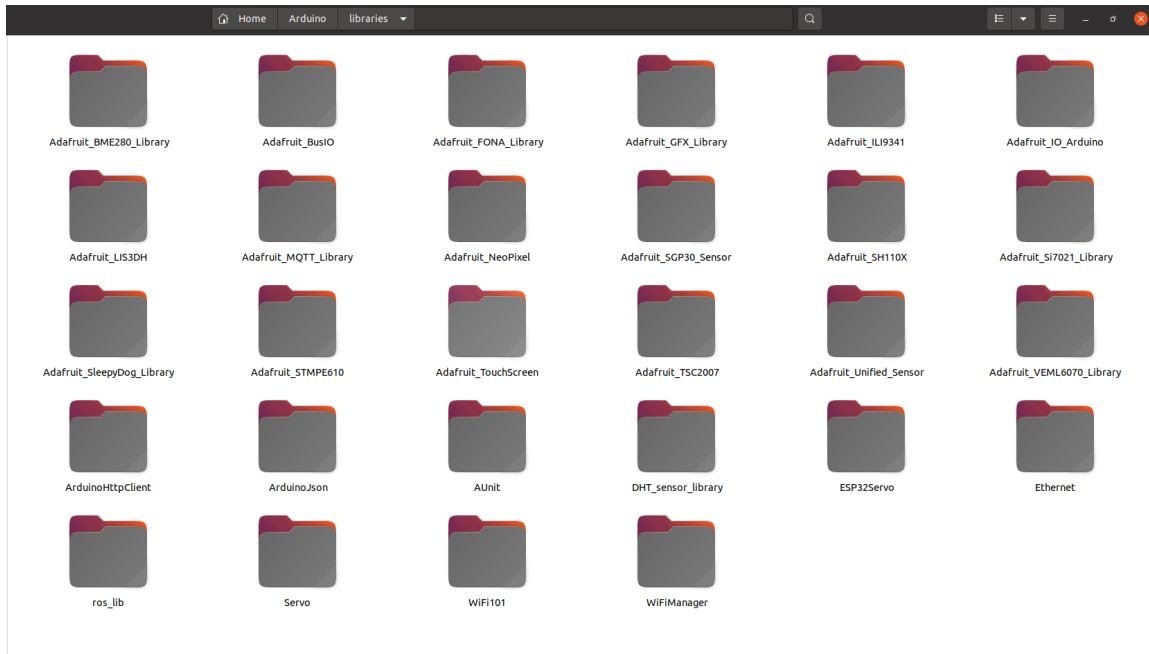


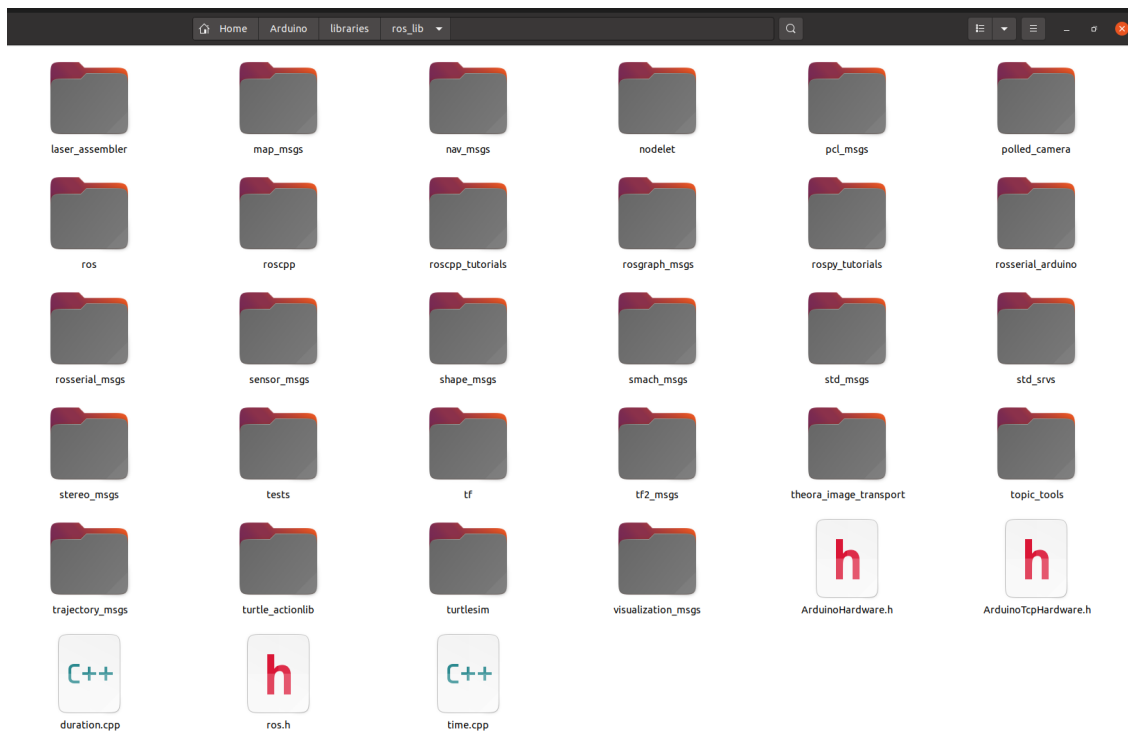
Attention please!!!

To ensure that rosserial over USB is working you must do the following:

1. go to Arduino folder Then libraries

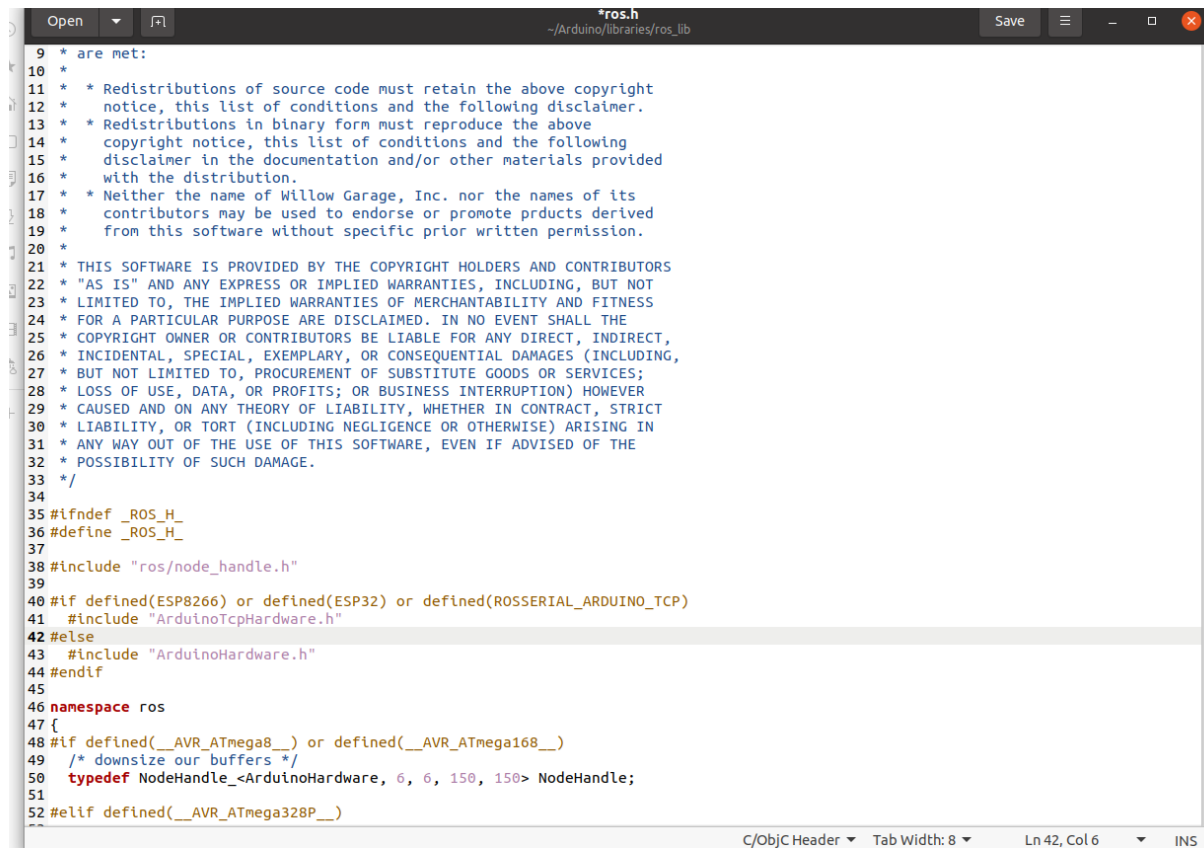


2. go to ros_lib folder to change ros.h file



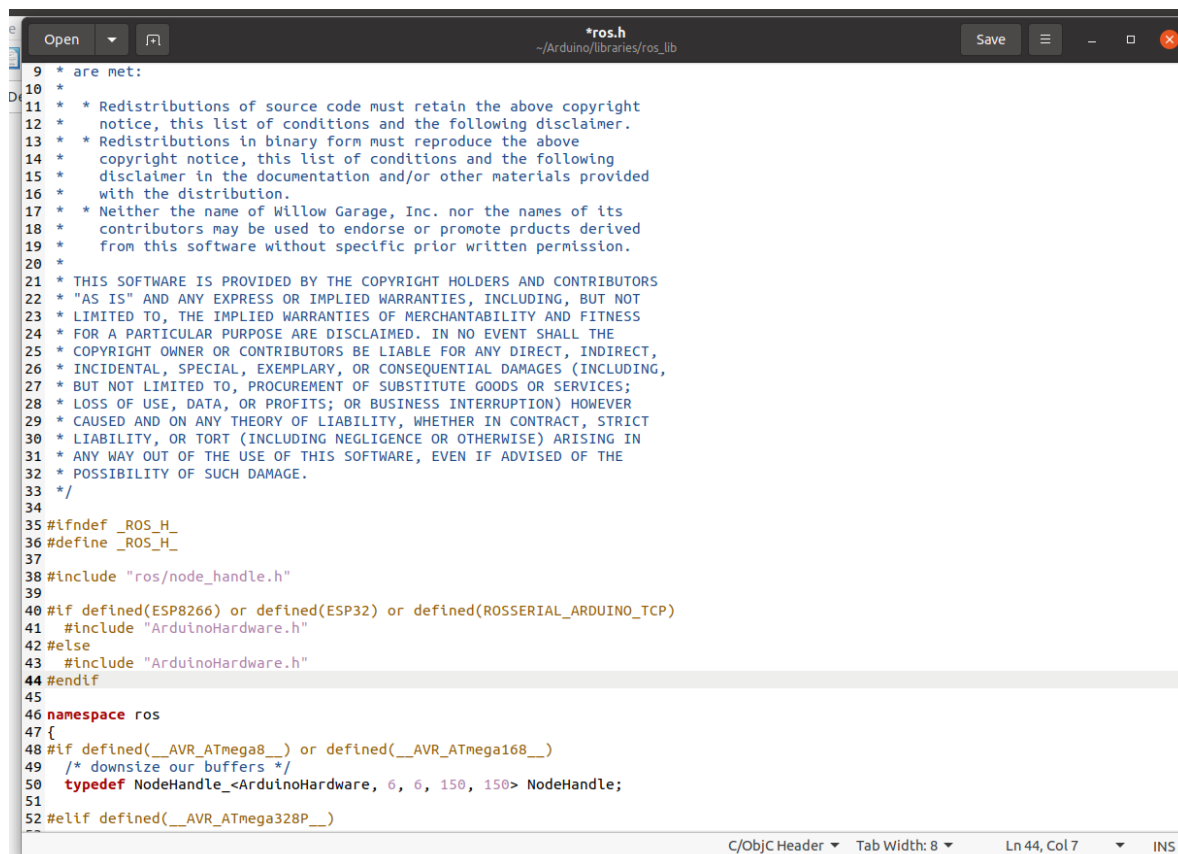
3. inside ros.h file you should change the following:

```
#if defined(ESP8266) or defined(ESP32) or defined(ROSSERIAL_ARDUINO_TCP)
#include "ArduinoTcpHardware.h"
#else
#include "ArduinoHardware.h"
#endif
```

A screenshot of an IDE window titled '*ros.h' with the path '~/Arduino/libraries/ros_lib'. The code is a C++ header file for ROS. Lines 9-34 contain a multi-line comment about copyright and redistribution. Lines 35-44 show conditional compilation for ESP8266 and ESP32. Line 41 has a syntax error: '#include "ArduinoTcpHardware.h"' is preceded by a closing angle bracket '>' from the previous line's conditional compilation, which is not closed. The IDE highlights this line in red. The status bar at the bottom shows 'C/ObjC Header', 'Tab Width: 8', 'Ln 42, Col 6', and 'INS'.

To:

```
#if defined(ESP8266) or defined(ESP32) or defined(ROSSERIAL_ARDUINO_TCP)
#include "ArduinoHardware.h"
#else
#include "ArduinoHardware.h"
#endif
```

```
9 * are met:
10 *
11 * * Redistributions of source code must retain the above copyright
12 * notice, this list of conditions and the following disclaimer.
13 * * Redistributions in binary form must reproduce the above
14 * copyright notice, this list of conditions and the following
15 * disclaimer in the documentation and/or other materials provided
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17 * * Neither the name of Willow Garage, Inc. nor the names of its
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21 * THIS SOFTWARE IS PROVIDED BY THE COPYRIGHT HOLDERS AND CONTRIBUTORS
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23 * LIMITED TO, THE IMPLIED WARRANTIES OF MERCHANTABILITY AND FITNESS
24 * FOR A PARTICULAR PURPOSE ARE DISCLAIMED. IN NO EVENT SHALL THE
25 * COPYRIGHT OWNER OR CONTRIBUTORS BE LIABLE FOR ANY DIRECT, INDIRECT,
26 * INCIDENTAL, SPECIAL, EXEMPLARY, OR CONSEQUENTIAL DAMAGES (INCLUDING,
27 * BUT NOT LIMITED TO, PROCUREMENT OF SUBSTITUTE GOODS OR SERVICES;
28 * LOSS OF USE, DATA, OR PROFITS; OR BUSINESS INTERRUPTION) HOWEVER
29 * CAUSED AND ON ANY THEORY OF LIABILITY, WHETHER IN CONTRACT, STRICT
30 * LIABILITY, OR TORT (INCLUDING NEGLIGENCE OR OTHERWISE) ARISING IN
31 * ANY WAY OUT OF THE USE OF THIS SOFTWARE, EVEN IF ADVISED OF THE
32 * POSSIBILITY OF SUCH DAMAGE.
33 */
34
35 #ifndef _ROS_H_
36 #define _ROS_H_
37
38 #include "ros/node_handle.h"
39
40 #if defined(ESP8266) or defined(ESP32) or defined(ROSSERIAL_ARDUINO_TCP)
41 #include "ArduinoHardware.h"
42 #else
43 #include "ArduinoHardware.h"
44 #endif
45
46 namespace ros
47 {
48 #if defined(__AVR_ATmega8__) or defined(__AVR_ATmega168__)
49 /* downsize our buffers */
50 typedef NodeHandle_<ArduinoHardware, 6, 6, 150, 150> NodeHandle;
51
52 #elif defined(__AVR_ATmega328P__)
```

Second thing is very important
when connecting with rosserial serialnode.py you should make sure that
serial monitor is closed.

Credits to



Bopp1312 commented on Aug 23, 2021 • edited ▾

...

I had the same issue, in the ros_lib directory there is a file called ros.h
I modified my file to look like this so that the serial interface was used rather than the TCP one.

```
#if defined(ESP8266) or defined(ESP32) or defined(ROSSERIAL_ARDUINO_TCP)
  //#include "ArduinoTcpHardware.h"
  #include "ArduinoHardware.h"
#else
  #include "ArduinoHardware.h"
#endif
```

