

12.Bind device ID

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- 1.Device view command
2. Establish port mapping relationship
 - 2.1. Device binding
 - 2.2. Introduction to rule file syntax
3. Verify view
4. Bind USB port

When the robot uses two or more USB serial devices, the corresponding relationship between the device name and the device is not fixed, but is assigned in sequence according to the order in which the devices are connected to the system.

Inserting one device first and then another device can determine the relationship between the device and the device name, but it is very troublesome to plug and unplug the device every time the system starts. The serial port can be mapped to a fixed device name. Regardless of the insertion order, the device will be mapped to a new device name. We only need to use the new device name to read and write the device.

1.Device view command

View camera device parameters

Enter the following command in the terminal to view the corresponding relationship between the camera's pixel size and frame rate.

```
v4l2-ctl --list-formats-ext
```

```
jetson@yahboom: ~  
jetson@yahboom: ~ 83x41  
jetson@yahboom:~$ v4l2-ctl --list-formats-ext  
ioctl: VIDIOC_ENUM_FMT  
  Index       : 0  
  Type        : Video Capture  
  Pixel Format : 'YUYV'  
  Name        : YUYV 4:2:2  
    Size: Discrete 1280x720  
      Interval: Discrete 0.111s (9.000 fps)  
    Size: Discrete 640x480  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 352x288  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 320x240  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 176x144  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 160x120  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 1280x800  
      Interval: Discrete 0.111s (9.000 fps)  
  
  Index       : 1  
  Type        : Video Capture  
  Pixel Format : 'MJPG' (compressed)  
  Name        : Motion-JPEG  
    Size: Discrete 1280x720  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 640x480  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 352x288  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 320x240  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 176x144  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 160x120  
      Interval: Discrete 0.033s (30.000 fps)  
    Size: Discrete 1280x800  
      Interval: Discrete 0.033s (30.000 fps)
```

View device ID

1susb

As can be seen from the picture below, Astra depth camera has an official document for binding the device to the ID number of each device. Generally, the controller does not need to be bound, and it can mainly be bound to the PCB and radar.

```
jetson@yahboom: ~  
jetson@yahboom: ~ 83x41  
jetson@yahboom:~$ lsusb  
Bus 002 Device 002: ID 0bda:0411 Realtek Semiconductor Corp.  
Bus 002 Device 001: ID 1d6b:0003 Linux Foundation 3.0 root hub  
Bus 001 Device 003: ID 8087:0a2b Intel Corp.  
Bus 001 Device 009: ID c0f4:04e0  
Bus 001 Device 007: ID 413c:301a Dell Computer Corp.  
Bus 001 Device 005: ID 214b:7250  
Bus 001 Device 008: ID 2bc5:0403 ← Astra Depth Joy  
Bus 001 Device 006: ID 2bc5:0501 ← Astra RGB PCB  
Bus 001 Device 004: ID 05e3:0608 Genesys Logic, Inc. Hub  
Bus 001 Device 012: ID 1a86:7523 QinHeng Electronics HL-340 USB-Serial adapter ← laser  
Bus 001 Device 018: ID 0079:181c DragonRise Inc.  
Bus 001 Device 013: ID 10c4:ea60 Cygnal Integrated Products, Inc. CP210x UART Bridge / myAVR mySmartUSB light  
Bus 001 Device 010: ID 2109:2813 VIA Labs, Inc.  
Bus 001 Device 002: ID 0bda:5411 Realtek Semiconductor Corp.  
Bus 001 Device 001: ID 1d6b:0002 Linux Foundation 2.0 root hub  
jetson@yahboom:~$
```

View device ID

11 /dev/

```

jetson@yahboom: ~ 117x43
crw----- 1 root root 3, 10 12月 10 17:15 ttya
crw----- 1 root root 3, 11 12月 10 17:15 ttyb
crw----- 1 root root 3, 12 12月 10 17:15 ttyc
crw----- 1 root root 3, 13 12月 10 17:15 ttyd
crw----- 1 root root 3, 14 12月 10 17:15 ttye
crw----- 1 root root 3, 15 12月 10 17:15 ttyf
crw--w---- 1 root tty 4, 64 2月 14 18:01 ttyS0
crw-rw---- 1 root dialout 4, 65 12月 10 17:15 ttyS1
crw-rw---- 1 root dialout 4, 66 12月 10 17:15 ttyS2
crw-rw---- 1 root dialout 4, 67 12月 10 17:15 ttyS3
crw--w---- 1 root tty 238, 1 2月 14 18:01 ttyTHS1
crw-rw---- 1 root dialout 238, 2 12月 10 17:15 ttyTHS2
crwxrwxrwx 1 root dialout 188, 0 12月 10 17:15 ttyUSB0 ← PCB
crwxrwxrwx 1 root dialout 188, 1 2月 14 18:01 ttyUSB1 ← laser
crw----- 1 root root 10, 239 12月 10 17:15 uhid
crw----- 1 root root 10, 223 12月 10 17:15 uinput
crw-rw-rw- 1 root root 1, 9 12月 10 17:15 urandom
drwxr-xr-x 4 root root 80 12月 10 17:15 v4l/
crw-rw---- 1 root tty 7, 0 12月 10 17:15 vcs
crw-rw---- 1 root tty 7, 1 12月 10 17:15 vcs1
crw-rw---- 1 root tty 7, 2 12月 10 17:15 vcs2
crw-rw---- 1 root tty 7, 3 12月 10 17:15 vcs3
crw-rw---- 1 root tty 7, 4 12月 10 17:15 vcs4
crw-rw---- 1 root tty 7, 5 12月 10 17:15 vcs5
crw-rw---- 1 root tty 7, 6 12月 10 17:15 vcs6
crw-rw---- 1 root tty 7, 128 12月 10 17:15 vcsa
crw-rw---- 1 root tty 7, 129 12月 10 17:15 vcsa1
crw-rw---- 1 root tty 7, 130 12月 10 17:15 vcsa2
crw-rw---- 1 root tty 7, 131 12月 10 17:15 vcsa3
crw-rw---- 1 root tty 7, 132 12月 10 17:15 vcsa4
crw-rw---- 1 root tty 7, 133 12月 10 17:15 vcsa5
crw-rw---- 1 root tty 7, 134 12月 10 17:15 vcsa6
drwxr-xr-x 2 root root 60 1月 1 1970 vfio/
crw----- 1 root root 10, 137 12月 10 17:15 vhci
crw-rw----+ 1 root video 81, 0 12月 10 17:15 video0 ← Astra
crw----- 1 root root 10, 130 12月 10 17:15 watchdog
crw----- 1 root root 244, 0 12月 10 17:15 watchdog0
crw-rw-rw- 1 root root 1, 5 12月 10 17:15 zero
brw-rw---- 1 root disk 252, 0 2月 14 18:01 zram0
brw-rw---- 1 root disk 252, 1 2月 14 18:01 zram1
brw-rw---- 1 root disk 252, 2 2月 14 18:01 zram2
brw-rw---- 1 root disk 252, 3 2月 14 18:01 zram3
jetson@yahboom:~$

```

2. Establish port mapping relationship

2.1. Device binding

- Astra binding

There is a create_udev_rules file in the scripts folder under the astra_camera function package.

Run this file to automatically bind it.

Run the command as follows

```
./create_udev_rules
```

Enter rules.d directory

```
cd /etc/udev/rules.d/
```

You can find the 56-orbbec-usb.rules file, which is the Astra camera device binding file.

- PCB and lidar binding

Enter rules.d directory

```
cd /etc/udev/rules.d/
```

Create a new rplidar.rules file

```
sudo touch rplidar.rules
sudo chmod 777 rplidar.rules
```

Open the rplidar.rules file

```
sudo vim rplidar.rules
```

Write the following content

```
KERNEL=="ttyUSB*", ATTRS{idVendor}=="1a86", ATTRS{idProduct}=="7523",
MODE:="0777", SYMLINK+="myserial"
KERNEL=="ttyUSB*", ATTRS{idVendor}=="10c4", ATTRS{idProduct}=="ea60",
MODE:="0777", SYMLINK+="rplidar"
```

Exit for the rules to take effect

```
sudo udevadm trigger
sudo service udev reload
sudo service udev restart
```

2.2. Introduction to rule file syntax

```
KERNEL=="ttyUSB*", ATTRS{idVendor}=="1a86", ATTRS{idProduct}=="7523",
MODE:="0777", SYMLINK+="myserial"
KERNEL=="ttyUSB*", ATTRS{idVendor}=="10c4", ATTRS{idProduct}=="ea60",
MODE:="0777", SYMLINK+="rplidar"
```

Analyze

KERNEL	#The device name matching the event
ATTR{filename}	# Match the sysfs attributes of the event device.
idVendor	# Manufacturer number
idProduct	# Product number
SYMLINK	# Generate symbolic links for device files under /dev/.
Just give this device an alias.	
MODE	# Set permissions for the device.

From [6.1], we can see that the PCB device number is [ttyUSB0] and is easy to change. The ID number is [1a86, 7523] and is fixed. [ttyUSB*] means that no matter the device number becomes [ttyUSB] in the future, it will be followed by [0, 1, 2, 3, 4,...] are all bound to [myserial]; the radar device [ttyUSB1] is the same; the same is true for other devices that need to be bound.

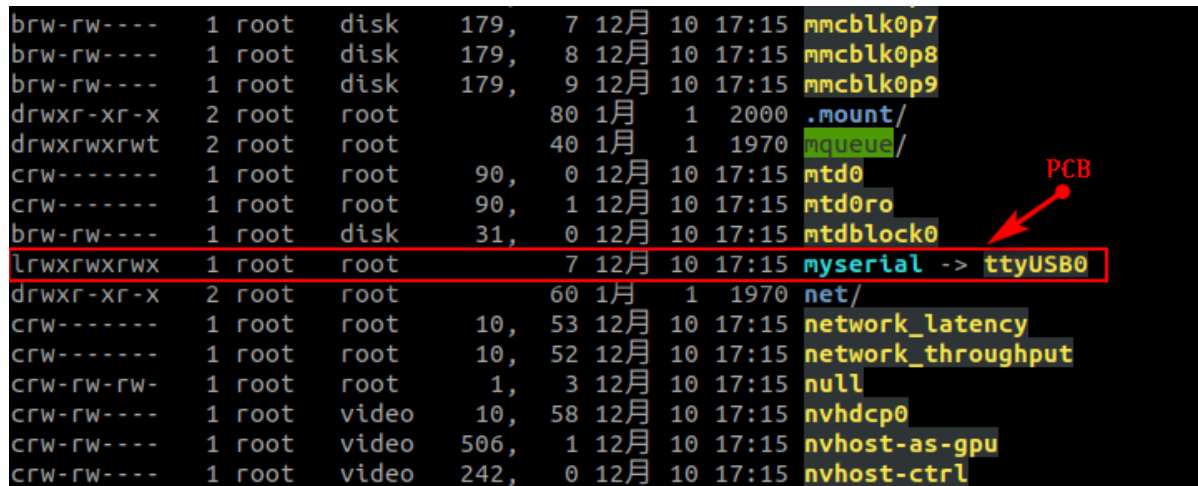
3. Verify view

View device number

```
11 /dev/
```

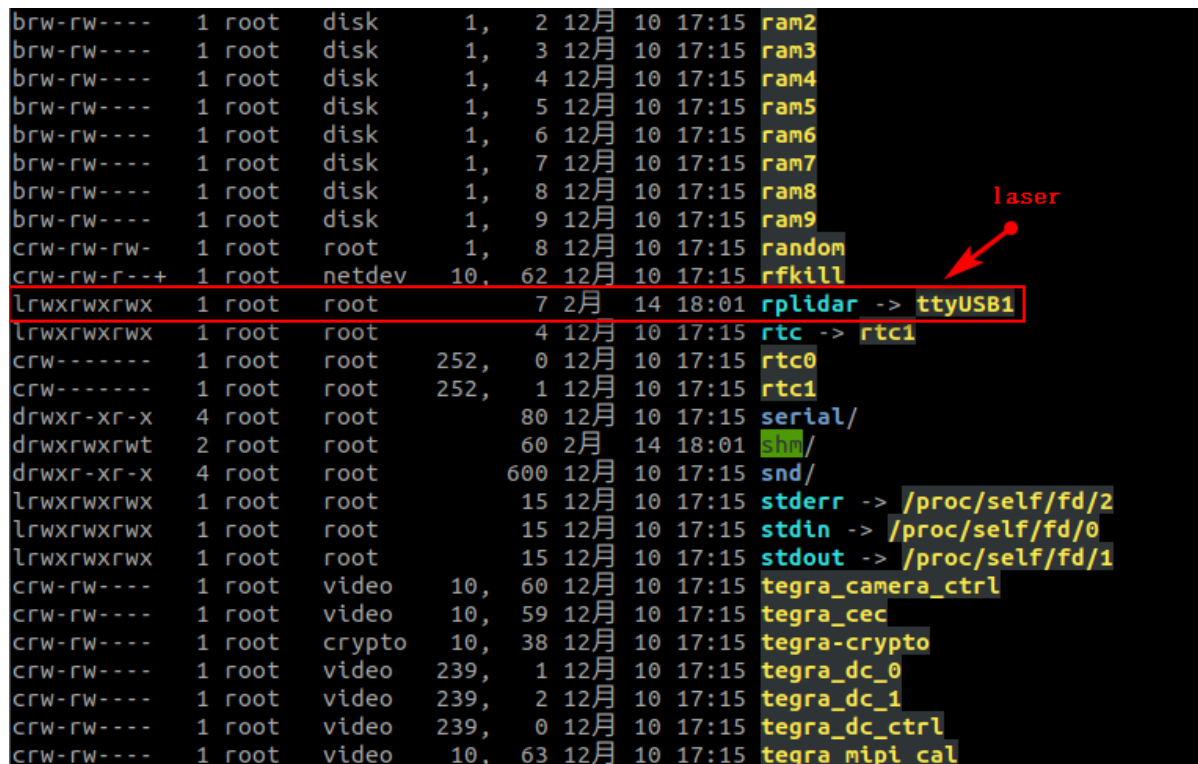
PCB

```
brw-rw---- 1 root disk 179, 7 12月 10 17:15 mmcblk0p7
brw-rw---- 1 root disk 179, 8 12月 10 17:15 mmcblk0p8
brw-rw---- 1 root disk 179, 9 12月 10 17:15 mmcblk0p9
drwxr-xr-x 2 root root 80 1月 1 2000 .mount/
drwxrwxrwt 2 root root 40 1月 1 1970 mqueue/
crw----- 1 root root 90, 0 12月 10 17:15 mtd0
crw----- 1 root root 90, 1 12月 10 17:15 mtd0ro
brw-rw---- 1 root disk 31, 0 12月 10 17:15 mtdblock0
lrwxrwxrwx 1 root root 7 12月 10 17:15 myserial -> ttyUSB0
drwxr-xr-x 2 root root 60 1月 1 1970 net/
crw----- 1 root root 10, 53 12月 10 17:15 network_latency
crw----- 1 root root 10, 52 12月 10 17:15 network_throughput
crw-rw-rw- 1 root root 1, 3 12月 10 17:15 null
crw-rw-rw- 1 root video 10, 58 12月 10 17:15 nvhdcp0
crw-rw-rw- 1 root video 506, 1 12月 10 17:15 nvhost-as-gpu
crw-rw-rw- 1 root video 242, 0 12月 10 17:15 nvhost-ctrl
```



laser

```
brw-rw---- 1 root disk 1, 2 12月 10 17:15 ram2
brw-rw---- 1 root disk 1, 3 12月 10 17:15 ram3
brw-rw---- 1 root disk 1, 4 12月 10 17:15 ram4
brw-rw---- 1 root disk 1, 5 12月 10 17:15 ram5
brw-rw---- 1 root disk 1, 6 12月 10 17:15 ram6
brw-rw---- 1 root disk 1, 7 12月 10 17:15 ram7
brw-rw---- 1 root disk 1, 8 12月 10 17:15 ram8
brw-rw---- 1 root disk 1, 9 12月 10 17:15 ram9
crw-rw-rw- 1 root root 1, 8 12月 10 17:15 random
crw-rw-rw-+ 1 root netdev 10, 62 12月 10 17:15 rfkill
lrwxrwxrwx 1 root root 7 2月 14 18:01 rplidar -> ttyUSB1
lrwxrwxrwx 1 root root 4 12月 10 17:15 rtc -> rtc1
crw----- 1 root root 252, 0 12月 10 17:15 rtc0
crw----- 1 root root 252, 1 12月 10 17:15 rtc1
drwxr-xr-x 4 root root 80 12月 10 17:15 serial/
drwxrwxrwt 2 root root 60 2月 14 18:01 shm/
drwxr-xr-x 4 root root 600 12月 10 17:15 snd/
lrwxrwxrwx 1 root root 15 12月 10 17:15 stderr -> /proc/self/fd/2
lrwxrwxrwx 1 root root 15 12月 10 17:15 stdin -> /proc/self/fd/0
lrwxrwxrwx 1 root root 15 12月 10 17:15 stdout -> /proc/self/fd/1
crw-rw-rw- 1 root video 10, 60 12月 10 17:15 tegra_camera_ctrl
crw-rw-rw- 1 root video 10, 59 12月 10 17:15 tegra_cec
crw-rw-rw- 1 root crypto 10, 38 12月 10 17:15 tegra-crypto
crw-rw-rw- 1 root video 239, 1 12月 10 17:15 tegra_dc_0
crw-rw-rw- 1 root video 239, 2 12月 10 17:15 tegra_dc_1
crw-rw-rw- 1 root video 239, 0 12月 10 17:15 tegra_dc_ctrl
crw-rw-rw- 1 root video 10, 63 12月 10 17:15 tegra_mipi_cal
```



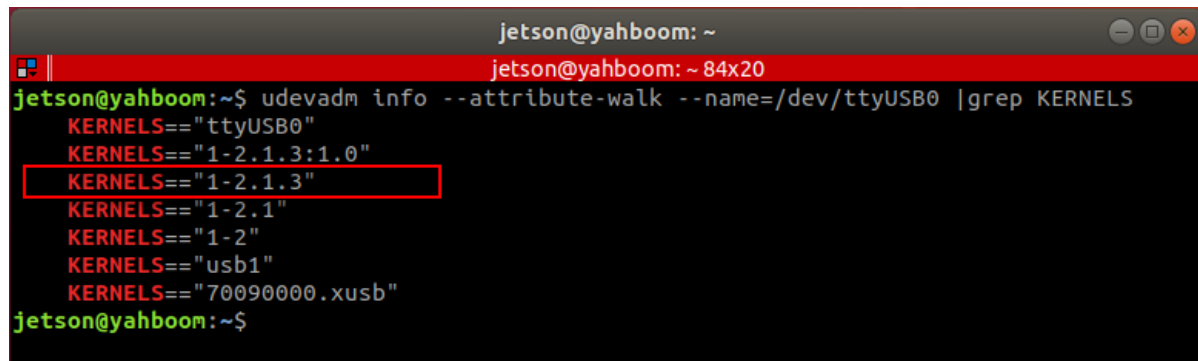
4. Bind USB port

The above situations are all different ID numbers. If the ID numbers of the radar and PCB are the same, or there are two or more PCBs (radars) with the same ID, the above binding will be confusing.

Then, we need to bind the USB port. After binding, the USB port cannot be changed at will. Each device can only be connected to a fixed USB port.

Binding method, take [ttyUSB0] as an example to check the port of the device at this time

```
udevadm info --attribute-walk --name=/dev/ttyUSB0 |grep KERNELS
```

A terminal window titled 'jetson@yahboom: ~' with a red header bar. The terminal shows the command 'udevadm info --attribute-walk --name=/dev/ttyUSB0 |grep KERNELS' being executed. The output lists several kernel names: 'KERNELS=="ttyUSB0"', 'KERNELS=="1-2.1.3:1.0"', 'KERNELS=="1-2.1.3"' (highlighted with a red box), 'KERNELS=="1-2.1"', 'KERNELS=="1-2"', 'KERNELS=="usb1"', and 'KERNELS=="70090000.xusb"'. The prompt 'jetson@yahboom:~\$' is visible at the bottom.

```
jetson@yahboom:~$ udevadm info --attribute-walk --name=/dev/ttyUSB0 |grep KERNELS
KERNELS=="ttyUSB0"
KERNELS=="1-2.1.3:1.0"
KERNELS=="1-2.1.3"
KERNELS=="1-2.1"
KERNELS=="1-2"
KERNELS=="usb1"
KERNELS=="70090000.xusb"
jetson@yahboom:~$
```

We need is to modify it in the rules file

```
# KERNEL=="ttyUSB*", ATTRS{idVendor}=="1a86", ATTRS{idProduct}=="7523",
MODE:="0777", SYMLINK+="myserial"      # before modify
KERNELS=="1-2.1.3", ATTRS{idVendor}=="1a86", ATTRS{idProduct}=="7523",
MODE:="0777", SYMLINK+="myserial"      # after modify
```