

```
#!/usr/bin/env python
```

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```

```
import rospy
from roserial_arduino import SerialClient
from serial import SerialException
from time import sleep
```

```
import sys
```

```
if __name__=="__main__":
```

```
    rospy.init_node("serial_node")
    rospy.loginfo("ROS Serial Python Node")
```

```
    port_name = rospy.get_param('~port','/dev/ttyUSB0')
    baud = int(rospy.get_param('~baud','57600'))
```

```
    # Number of seconds of sync failure after which Arduino is auto-reset.
    # 0 = no timeout, auto-reset disabled
    auto_reset_timeout = int(rospy.get_param('~auto_reset_timeout','0'))
```

```
    # for systems where pyserial yields errors in the fcntl.ioctl(self.fd, TIOCMBS, \
    # TIOCM_DTR_str) line, which causes an IOError, when using simulated port
    fix_pyserial_for_test = rospy.get_param('~fix_pyserial_for_test', False)
```

```
    # TODO: do we really want command line params in addition to parameter server params?
    sys.argv = rospy.myargv(argv=sys.argv)
    if len(sys.argv) >= 2 :
        port_name = sys.argv[1]
```

```
    while not rospy.is_shutdown():
        rospy.loginfo("Connecting to %s at %d baud" % (port_name, baud))
        try:
            client = SerialClient(port_name, baud, fix_pyserial_for_test=fix_pyserial_for_t
est, auto_reset_timeout=auto_reset_timeout)
```

```
        client.run()
    except KeyboardInterrupt:
        break
    except SerialException:
        sleep(1.0)
        continue
    except OSError:
        sleep(1.0)
        continue
```