

# NI-DAQ Broadcasting to ROS

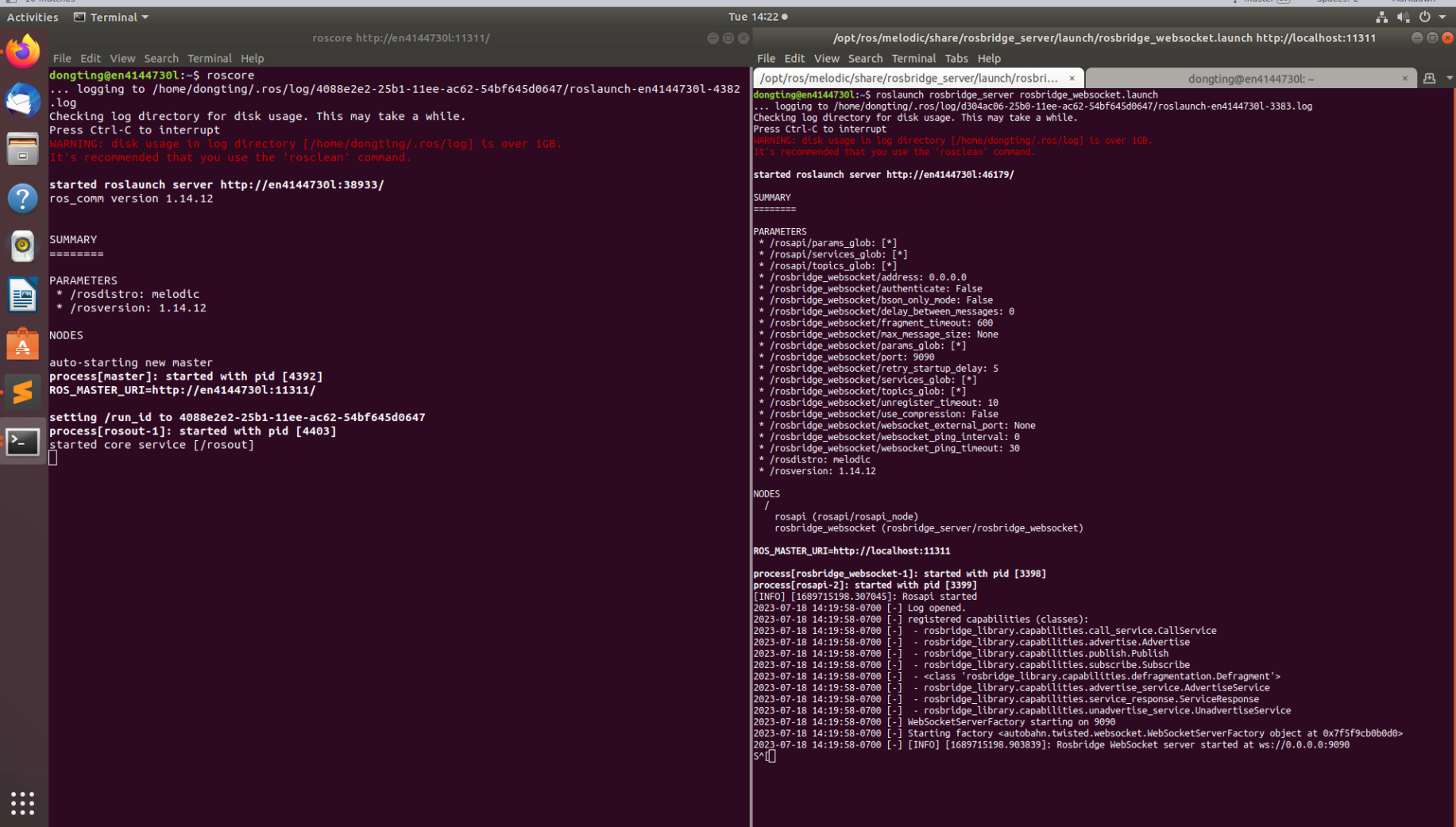
## 1: Broadcasting NI-DAQ from Windows to ROS

This part is a little bit tricky, as you need first start `roscore` then start the python script in windows.

### 1.1: Step by step:

```
roscore
roslaunch rosbridge_server rosbridge_websocket.launch
```

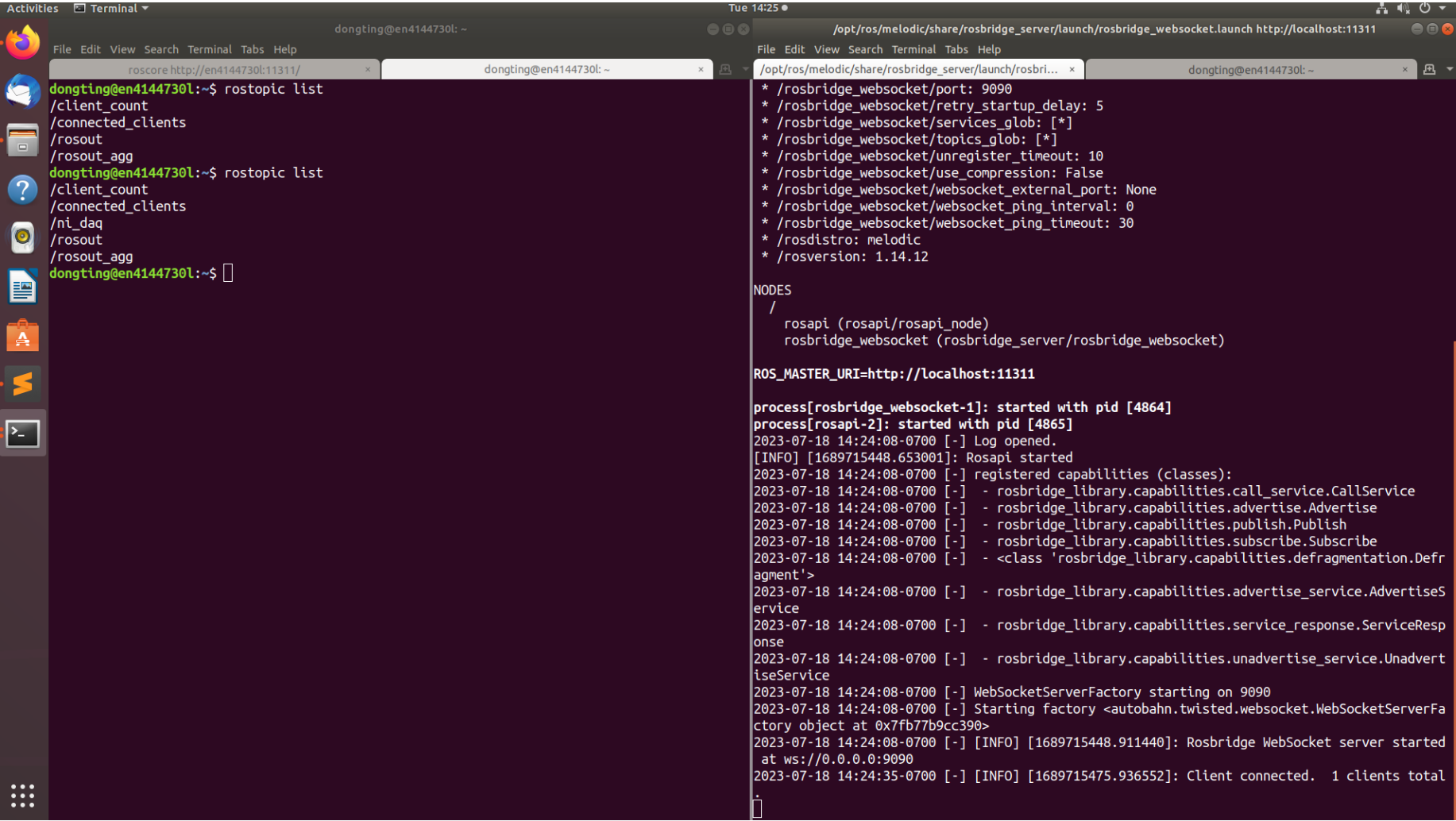
And your terminal will be like this.



After that, you can see at the bottom, it says: rosbridge websocket server started at ...

The in windows, to start.

```
python ros_ni_daq_talker.py
```



### 1.2: Code locations

1. windows side: checkout [code\\_equipment](#). The windows python script is located in `code_equipment/python/idealab_equipment/ros_ni_daq_talker.py`
2. Linux side: checkout [rosbridge\\_suite](#) ros1 branch

## 1.3: note

1. you might want to adjust the buffer and sample rate to get things working. I tested up to 40k hz for 4 channels and it should be covering most of the case.