**UDP Transport**

Configuring the firmware

*ros2 run micro\_ros\_setup configure\_firmware.sh [PROJECT NAME] -t udp -i [LOCAL MACHINE IP ADDRESS] -p 8888*

Steps to run a micro-ros program

1. Build

*ros2 run micro\_ros\_setup build\_firmware.sh*

2. Flash

*ros2 run micro\_ros\_setup flash\_firmware.sh*

3. Create Agent

*# Download micro-ROS-Agent packages  
 ros2 run micro\_ros\_setup create\_agent\_ws.sh*

4. Build Agent

*# Build step  
 ros2 run micro\_ros\_setup build\_agent.sh  
 source install/local\_setup.bash*

5. Run ROS agent

*# Run a micro-ROS agent  
 ros2 run micro\_ros\_agent micro\_ros\_agent udp4 --port 8888*

**Serial Transport**

Configuring the firmware

*# Configure step with ping\_pong app and serial transport*

*ros2 run micro\_ros\_setup configure\_firmware.sh [your\_app] --transport serial*

*replace [your\_app] with the name of your application*

Build the firmware

*# Build step*

*ros2 run micro\_ros\_setup build\_firmware.sh*

Flash the firmware

*# Flash step ros2 run micro\_ros\_setup flash\_firmware.sh*

Create Agent

*# Download micro-ROS-Agent packages*

*ros2 run micro\_ros\_setup create\_agent\_ws.sh*

Build Agent

*# Build step*

*ros2 run micro\_ros\_setup build\_agent.sh*

*source install/local\_setup.bash*

Run the Agent

*# Run a micro-ROS agent*

*ros2 run micro\_ros\_agent micro\_ros\_agent serial --dev [device]*

Replace [device] with your serial connection *e.g* **/dev/ttyUSB0**