## fatal error: component\_interface\_utils/rclcpp.hpp does not exist #5408

Unanswered )

xcg340122 asked this question in Q&A



xcg340122 2 weeks ago

Hello, recently I was learning autoware.universe. I followed the tutorial and got an error when compiling autoware\_iv\_external\_api\_adaptor

Error message:fatal error: component\_interface\_utils/rclcpp.hpp does not exist

```
Starting >>> autoware_iv_external_api_adaptor
 -- stderr: autoware_iv_external_api_adaptor
In file included from /home/bylike/autoware/src/universe/external/tier4_ad_api_adaptor/autoware_iv_ex
aptor/src/route.cpp:15:
/home/bylike/autoware/src/universe/external/tier4_ad_api_adaptor/autoware_iv_external_api_adaptor/src
                 component_interface_utils/rclcpp.hpp: 没有那个文件或目录
   19 | #include
compilation terminated.
gmake[2]: *** [CMakeFiles/autoware_iv_external_api_adaptor.dir/build.make:258: CMakeFiles/autoware_iv
_adaptor.dir/src/route.cpp.o] 错误 1
gmake[2]: *** 正在等待未完成的任务...
In file included from /home/bylike/autoware/src/universe/external/tier4_ad_api_adaptor/autoware_iv_ex
aptor/src/initial pose.cpp:15:
/home/bylike/autoware/src/universe/external/tier4_ad_api_adaptor/autoware_iv_external_api_adaptor/src
.hpp:19:10:
                     pr: component_interface_utils/rclcpp.hpp: 没有那个文件或目录
   19 | #include
compilation terminated.
gmake[2]: *** [CMakeFiles/autoware_iv_external_api_adaptor.dir/build.make:174: CMakeFiles/autoware_iv
_adaptor.dir/src/initial_pose.cpp.o] 错误 1
gmake[1]: *** [CMakeFiles/Makefile2:137: CMakeFiles/autoware_iv_external_api_adaptor.dir/all] 错误 2
gmake: *** [Makefile:146: all] 错误 2
        <<< autoware_iv_external_api_adaptor [0.60s, exited with code 2]</pre>
Aborted <<< autoware_behavior_velocity_planner [45.0s]
```

When I update with 'rosdep install -y --from-paths src --ignore-src -rosdistro \$ROS\_DISTRO', the following message appears:

bylike@bylike-G3-3590:~/autoware\$ rosdep install -y --from-paths src --ignore-src --rosdistro \$ROS\_DISTRO ERROR: the following packages/stacks could not have their rosdep keys resolved to system dependencies: autoware\_iv\_external\_api\_adaptor: <u>C</u>annot locate rosdep definition for [component\_interface\_utils]



Category



Q&A

Labels

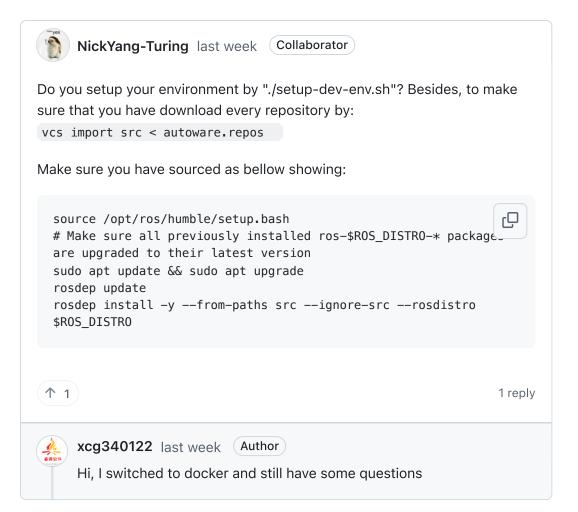
None yet

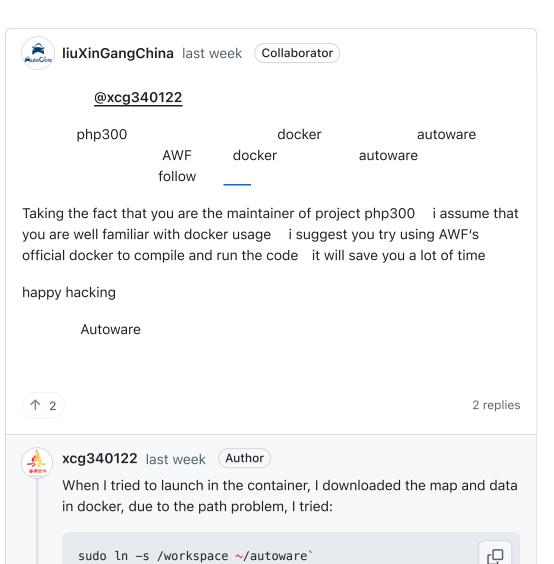
3 participants











source ~/autoware/install/setup.bash

ros2 launch autoware\_launch planning\_simulator.launch.xml map\_

The result is an infinite refresh error:

[component\_container\_mt-35] [ERROR] [1731682458.37140318 [planning.scenario\_planning.parking.costmap\_generator]: Could not find a connection between 'map' and 'base\_link' because they are not part of the same tree.Tf has two or more unconnected trees.

[component\_container\_mt-35] [ERROR] [1731682458.471267312] [planning.scenario\_planning.parking.costmap\_generator]: Could not find a connection between 'map' and 'base\_link' because they are not part of the same tree.Tf has two or more unconnected trees.

[component\_container\_mt-35] [ERROR] [1731682458.571292909] [planning.scenario\_planning.parking.costmap\_generator]: Could not find a connection between 'map' and 'base\_link' because they are not part of the same tree.Tf has two or more unconnected trees.

[component\_container\_mt-35] [ERROR] [1731682458.671303784] [planning.scenario\_planning.parking.costmap\_generator]: Could not find a connection between 'map' and 'base\_link' because they are not part of the same tree.Tf has two or more unconnected trees.

[component\_container\_mt-35] [ERROR] [1731682458.771211131] [planning.scenario\_planning.parking.costmap\_generator]: Could not find a connection between 'map' and 'base\_link' because they are not part of the same tree.Tf has two or more unconnected trees.

[component\_container\_mt-35] [ERROR] [1731682458.871079966] [planning.scenario\_planning.parking.costmap\_generator]: Could not find a connection between 'map' and 'base\_link' because they are not part of the same tree.Tf has two or more unconnected trees.

[component\_container\_mt-35] [ERROR] [1731682458.971047899] [planning.scenario\_planning.parking.costmap\_generator]: Could not find a connection between 'map' and 'base\_link' because they are not part of the same tree.Tf has two or more unconnected trees.

[component\_container\_mt-35] [ERROR] [1731682459.071058878] [planning.scenario\_planning.parking.costmap\_generator]: Could not find a connection between 'map' and 'base\_link' because they are not part of the same tree.Tf has two or more unconnected trees.

## Directory structure:

bylike@bylike-G3-3590:~/autoware\$ ls ~
autoware autoware\_data autoware\_map

Q

bylike@bylike-G3-3590:~/autoware\$ ls

CODE OF CONDUCT.md README.md build CONTRIBUTING.md amd64.env docker CPPLINT.cfg ansible install ansible-galaxy-requirements.yaml log DISCLAIMER.md LICENSE arm64.env setup-de NOTICE autoware.repos setup.cf

bylike@bylike-G3-3590:~/autoware\_data\$ ls ~/autoware\_data/image\_projection\_based\_fusion lidar\_transfusion

```
lidar_apollo_instance_segmentation tensorrt_yolox
lidar_centerpoint traffic_light_classifier

bylike@bylike-G3-3590:~/autoware_data$ ls ~/autoware_map/sampl
lanelet2_map.osm map_config.yaml map_projector_info.yaml pc
```



## xcg340122 5 days ago (Author)

It was recompiled again today

```
Finished <<< autoware_behavior_path_external_request_lane_change_module
Finished <<< autoware_behavior_path_avoidance_by_lane_change_module [5.1
Finished <<< control_performance_analysis [12.0s]
Finished <<< autoware_launch [4.83s]
Finished <<< autoware_motion_velocity_planner_node [8.83s]
Finished <<< autoware_static_centerline_generator [9.51s]

Summary: 346 packages finished [2min 51s]

1 package had stderr output: autoware_carla_interface
root@bylike-G3-3590:/home/autoware#
```

Log of the failed package:

```
Starting >>> hazard_status_converter
--- stderr: autoware_carla_interface
/usr/local/lib/python3.10/dist-packages/setuptools/command/eas
warnings.warn(
---
Finished <<< autoware_carla_interface [4.62s]
```

Then I tried to run a planning simulation test:

```
root@bylike-G3-3590:/home/autoware# ros2 launch autoware [INFO] [launch]: All log files can be found below /root/.../l [INFO] [launch]: Default logging verbosity is set to INFO [ERROR] [launch]: Caught exception in launch (see debug for tr Captured stderr output: error: package not found: "package 'sa when processing file: /home/autoware/install/tier4_vehicle_lau [INFO] [component_container_mt-1]: process started with pid [4 [component_container_mt-1] [INFO] [1731803620.005108417] [poin [component_container_mt-1] [INFO] [1731803620.005108417] [poin [INFO] [component_container_mt-1]: sending signal 'SIGINT' to [component_container_mt-1] [INFO] [1731803620.168271020] [rclc [INFO] [component_container_mt-1]: process has finished cleanl [WARNING] [launch_ros.actions.load_composable_nodes]: Abandoni
```