

# 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_external_api_adaptor/src/route.cpp:15:
/home/bylike/autoware/src/universe/external/tier4_ad_api_adaptor/autoware_iv_external_api_adaptor/src/route.cpp:10: fatal error: component_interface_utils/rclcpp.hpp: 没有那个文件或目录
   19 | #include "component_interface_utils/rclcpp.hpp"
      |
compilation terminated.
gmake[2]: *** [CMakeFiles/autoware_iv_external_api_adaptor.dir/build.make:258: CMakeFiles/autoware_iv_external_api_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_external_api_adaptor/src/initial_pose.cpp:15:
/home/bylike/autoware/src/universe/external/tier4_ad_api_adaptor/autoware_iv_external_api_adaptor/src/initial_pose.cpp:19:10: fatal error: component_interface_utils/rclcpp.hpp: 没有那个文件或目录
   19 | #include <component_interface_utils/rclcpp.hpp>
      |
compilation terminated.
gmake[2]: *** [CMakeFiles/autoware_iv_external_api_adaptor.dir/build.make:174: CMakeFiles/autoware_iv_external_api_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
---
Failed <<< autoware_iv_external_api_adaptor [0.60s, exited with code 2]
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: Cannot locate rosdep definition for [component_interface_utils]
```

Category



Q&A

Labels

None yet

3 participants



↑ 1

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**NickYang-Turing** last week Collaborator

Do you setup your environment by `"./setup-dev-env.sh"`? Besides, to make sure that you have download every repository by:

```
vcs import src < autoware.repos
```

Make sure you have sourced as bellow showing:

```
source /opt/ros/humble/setup.bash
# Make sure all previously installed ros-$ROS_DISTRO-* packages
are upgraded to their latest version
sudo apt update && sudo apt upgrade
rosdep update
rosdep install -y --from-paths src --ignore-src --rosdistro
$ROS_DISTRO
```



↑ 1

1 reply



**xcg340122** last week Author

Hi, I switched to docker and still have some questions



**liuXinGangChina** last week Collaborator

@xcg340122

php300

docker

autoware

AWF

docker

autoware

follow

Taking the fact that you are the maintainer of project php300 i assume that you are well familiar with docker usage i suggest you try using AWF's official docker to compile and run the code it will save you a lot of time

happy hacking

Autoware

↑ 2

2 replies



**xcg340122** last week Author

When I tried to launch in the container, I downloaded the map and data in docker, due to the path problem, I tried:

```
sudo ln -s /workspace ~/autoware`
source ~/autoware/install/setup.bash
```



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

bylike@bylike-G3-3590:~/autoware$ ls
CODE_OF_CONDUCT.md  README.md          build
CONTRIBUTING.md    amd64.env          docker
CPPLINT.cfg         ansible            install
DISCLAIMER.md       ansible-galaxy-requirements.yaml  log
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/sample
lanelet2_map.osm  map_config.yaml  map_projector_info.yaml  po
```



**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/easy_install.py:425:
  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_planning_simulation
[INFO] [launch]: All log files can be found below /root/.ros/log/2024-08-10_15-10-10
[INFO] [launch]: Default logging verbosity is set to INFO
[ERROR] [launch]: Caught exception in launch (see debug for traceback): package 'sa
Captured stderr output: error: package not found: "package 'sa
when processing file: /home/autoware/install/tier4_vehicle_launch

[INFO] [component_container_mt-1]: process started with pid [4
[component_container_mt-1] [INFO] [1731803620.001785063] [poin
[component_container_mt-1] [INFO] [1731803620.005108417] [poin
[component_container_mt-1] [INFO] [1731803620.005125986] [poin
[INFO] [component_container_mt-1]: sending signal 'SIGINT' to
[component_container_mt-1] [INFO] [1731803620.168271020] [rcld
[INFO] [component_container_mt-1]: process has finished cleanl
[WARNING] [launch_ros.actions.load_composable_nodes]: Abandoni
```