

02. Linux, ROS alapismeretek

Elmélet

ROS 1 → ROS 2

- ROS 2 was rewritten from scratch
 - More modular architecture
 - Improved support for real-time systems
 - Support for multiple communication protocols
 - Better interoperability with other robotic systems
 - Focus on standardization and industry collaboration
 - No ROS Master
 - No Devel space
 - `rclpy`, `rclcpp`
 - More structured code (`Node` class)
 - Different build system
 - Platforms: Windows, OS X, Linux
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ROS principles

ROS node
