



## 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
- 

#### ROS principles

---

---

#### ROS node

---