02. Linux, ROS introduction

Lecture

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