



## 02. Linux, ROS introduction

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### Lecture

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#### ROS 1 → ROS 2

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- 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

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#### ROS node

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