ROS2環境需求

* **系統環境**
  + OS: Ubuntu 22.04 or Ubuntu 20.04 (x64)
  + RAM: 16GB or higher
  + WLAN: 1Gbps or higher
* **ROS2 Distro**
  + \*Humble (Ubuntu 22.04)
  + Foxy (Ubuntu 20.04)

\*: recommended

* **ROS2 Installation**
  + Humble installation guide: [docs.ros.org](https://docs.ros.org/en/humble/Installation/Ubuntu-Install-Debians.html)
  + Foxy installation guide: [docs.ros.org](https://docs.ros.org/en/foxy/Installation/Ubuntu-Install-Debians.html)
    - If using foxy distro, after installation completed, highly recommended replace parameter.py from [here](https://github.com/ros2/rclpy/blob/humble/rclpy/rclpy/parameter.py) (humble distro).
    - The default parameter.py location: /opt/ros/foxy/lib/python3.8/site-packages/rclpy/parameter.py
* **ROS2 Tutorials (Humble Distro)**
  + \*Topic (one publisher and multiple subscribers)
    - C++: [docs.ros.org](https://docs.ros.org/en/humble/Tutorials/Beginner-Client-Libraries/Writing-A-Simple-Cpp-Publisher-And-Subscriber.html)
    - Python3: [docs.ros.org](https://docs.ros.org/en/humble/Tutorials/Beginner-Client-Libraries/Writing-A-Simple-Py-Publisher-And-Subscriber.html)
  + Service (one server and multiple clients)
    - C++: [docs.ros.org](https://docs.ros.org/en/humble/Tutorials/Beginner-Client-Libraries/Writing-A-Simple-Cpp-Service-And-Client.html)
    - Python3: [docs.ros.org](https://docs.ros.org/en/humble/Tutorials/Beginner-Client-Libraries/Writing-A-Simple-Py-Service-And-Client.html)
  + Custom Interfaces
    - Create interfaces: [docs.ros.org](https://docs.ros.org/en/humble/Tutorials/Beginner-Client-Libraries/Custom-ROS2-Interfaces.html)
    - Implement custom interfaces: [docs.ros.org](https://docs.ros.org/en/humble/Tutorials/Beginner-Client-Libraries/Single-Package-Define-And-Use-Interface.html)
  + ROS2 Launch File
    - Create launch file: [docs.ros.org](https://docs.ros.org/en/humble/Tutorials/Intermediate/Launch/Creating-Launch-Files.html)

\*: Commonly used for sensor message