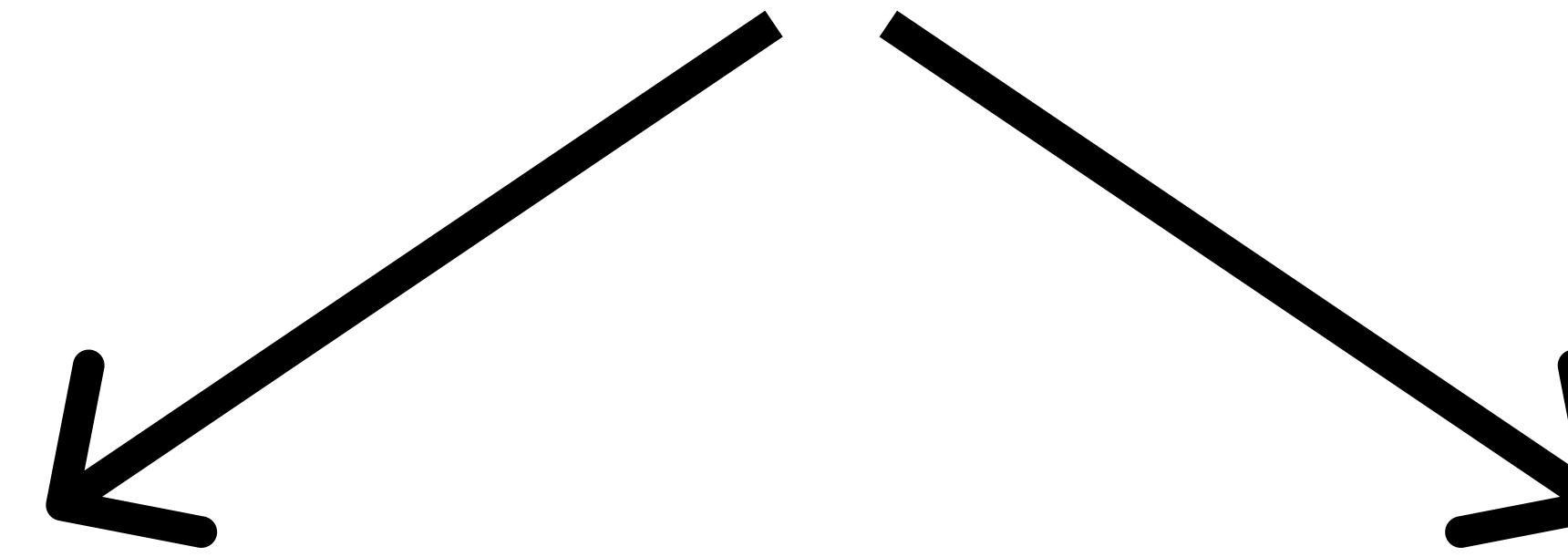
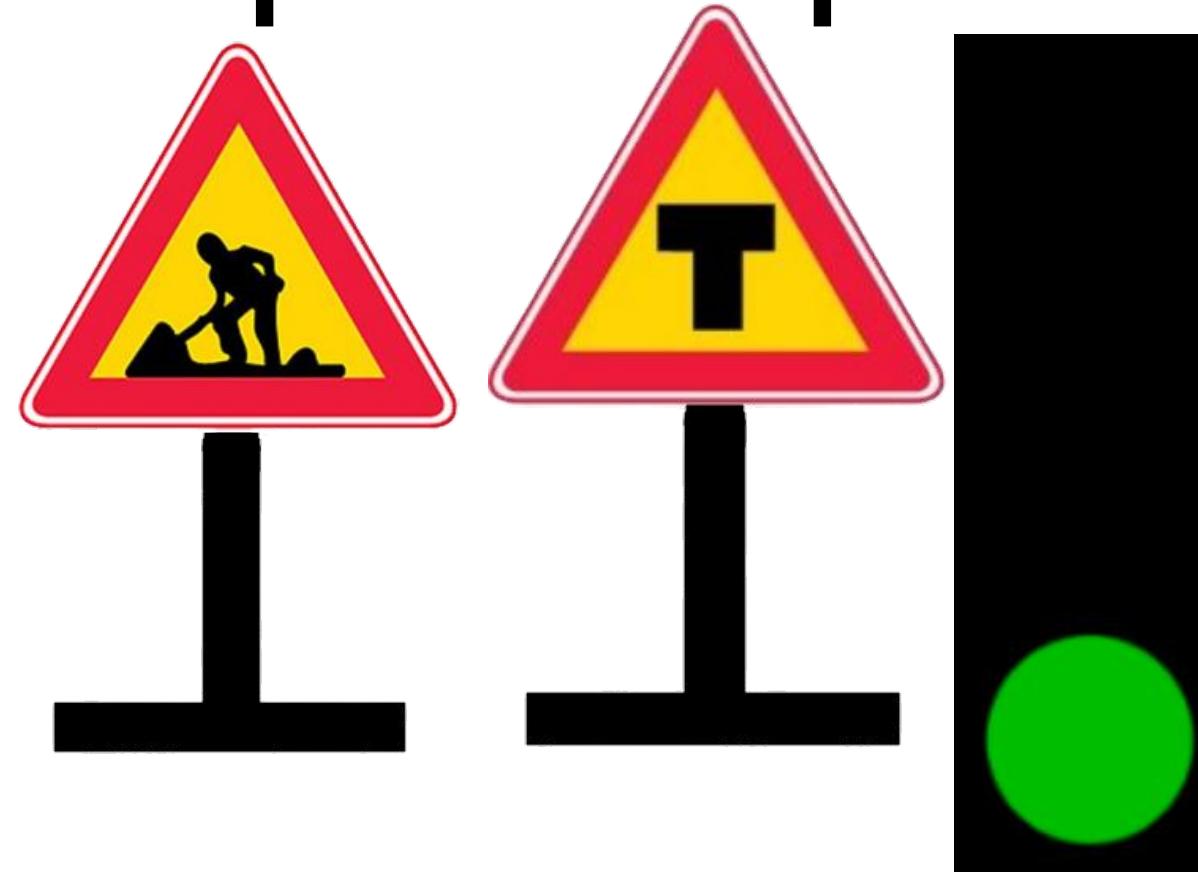


**ROS-pypyjni**

# два ключевых узла



perception\_node



lane\_follower





