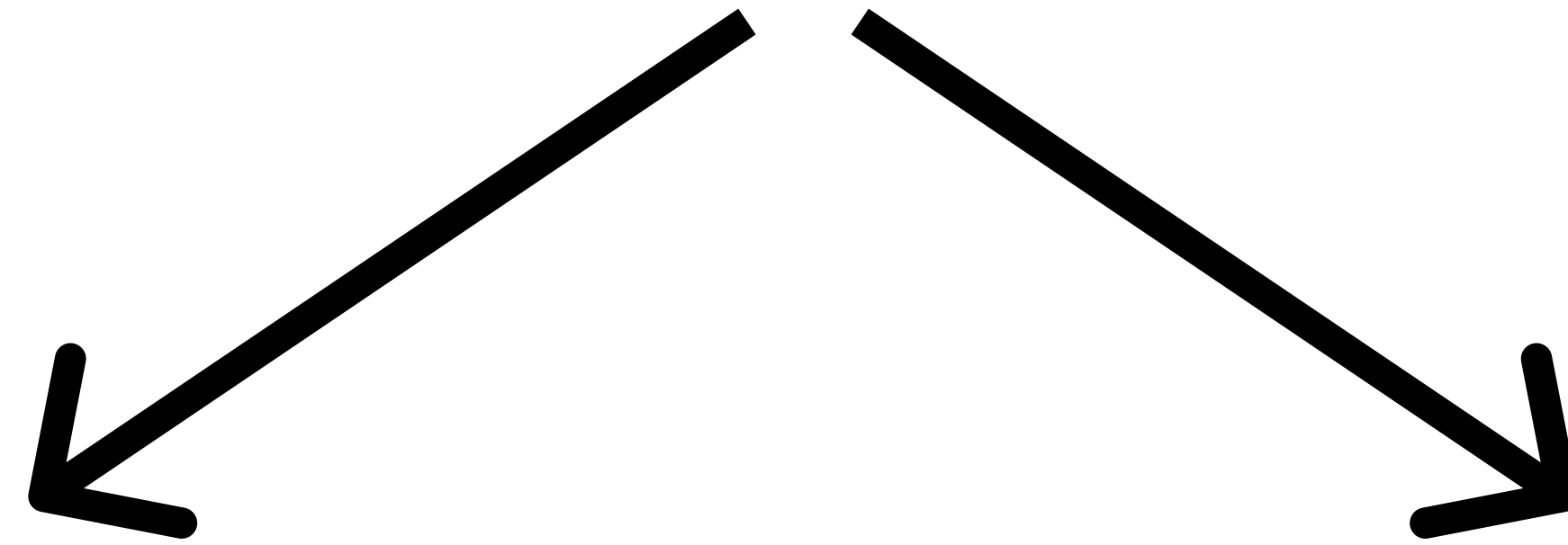
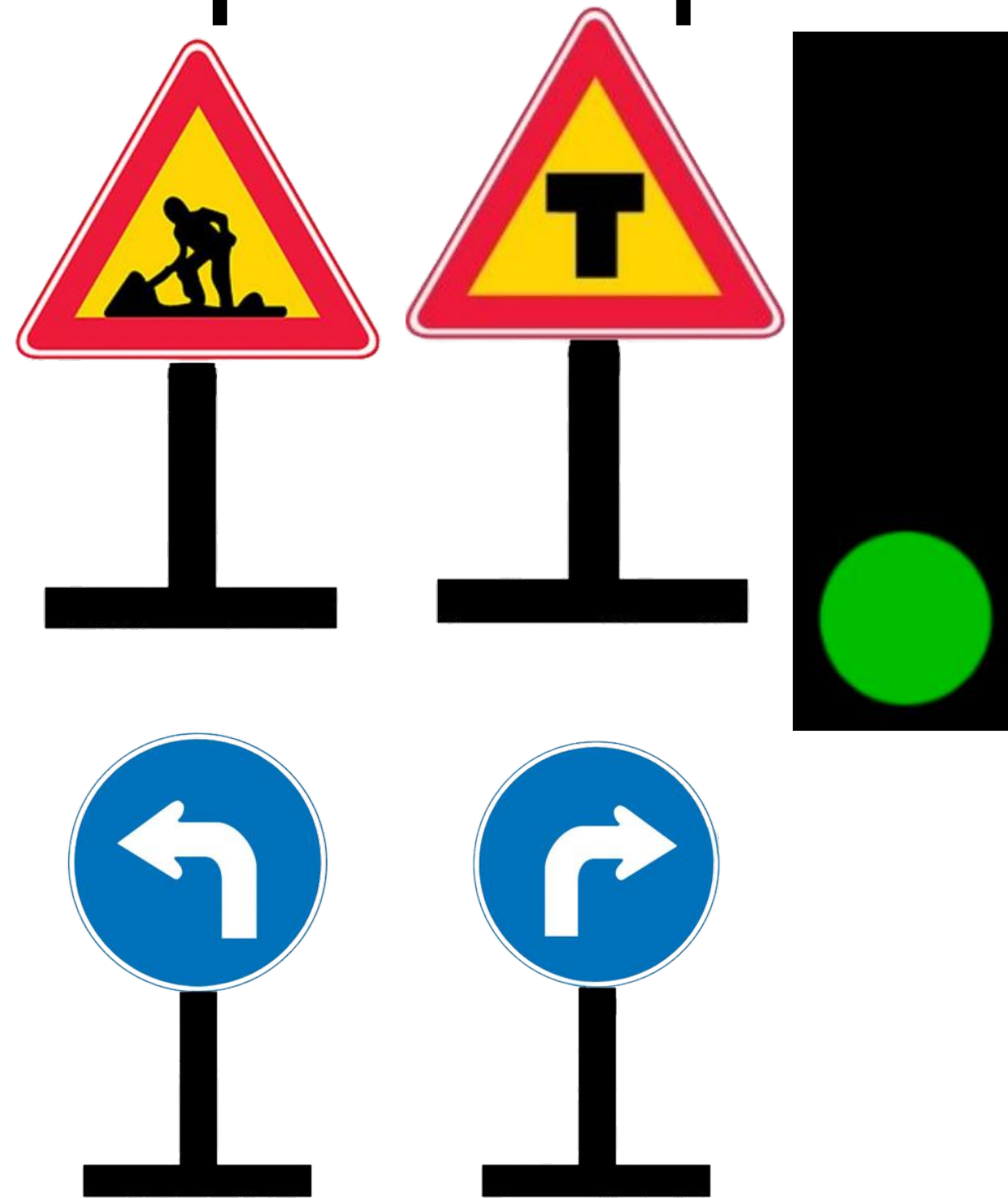


ROS-pypyni

# Два ключевых узла



perception\_node



lane\_follower

