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1. See Also:















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2. What is a Distribution?

A ROS distribution is a versioned set of ROS packages. These are akin to Linux distributions (e.g. Ubuntu). The purpose of the ROS distributions is to let developers work against a relatively stable codebase until they are ready to roll everything forward. Therefore once a distribution is released, we try to limit changes to bug fixes and non-breaking improvements for the core packages (every thing under `ros-desktop-full`). And generally that applies to the whole community, but for "higher" level packages, the rules are less strict, and so it falls to the maintainers of a given package to avoid breaking changes.

We capture the components that make up a distribution in our rosdistro (/rosdistro) format and it allows for multiple distributions. There are many different types of robots with different needs, and we anticipate that parts of the community may put together their own distributions in the future to better target these platforms.

3. List of Distributions

Distro	Release date	Poster	Tuturtle, turtle in tutorial	EOL date
ROS Noetic Ninjemys (/noetic) (Recommended)	May 23rd, 2020			May, 2025 (Focal EOL)
ROS Melodic Morenia (/melodic)	May 23rd, 2018	 (/melodic)		May, 2023 (Bionic EOL)
ROS Lunar Loggerhead (/lunar)	May 23rd, 2017	 (/lunar)		May, 2019
ROS Kinetic Kame (/kinetic)	May 23rd, 2016	 (/kinetic)		April, 2021 (Xenial EOL)
ROS Jade Turtle (/jade)	May 23rd, 2015	 (/jade)		May, 2017
ROS Indigo Igloo (/indigo)	July 22nd, 2014	 (/indigo)		April, 2019 (Trusty EOL)
ROS Hydro Medusa (/hydro)	September 4th, 2013	 (/hydro)		May, 2015

ROS Groovy Galapagos (/groovy)	December 31, 2012		(/groovy)		July, 2014
ROS Fuerte Turtle (/fuerte)	April 23, 2012		(/fuerte)		--
ROS Electric Emys (/electric)	August 30, 2011		(/electric)		--
ROS Diamondback (/diamondback)	March 2, 2011		(/diamondback)		--
ROS C Turtle (/cturtle)	August 2, 2010		(/cturtle)		--
ROS Box Turtle (/boxturtle)	March 2, 2010		(/boxturtle)		--
		⋮Box Turtle			

Legend

- light yellow: future release
- green: supported release
- grey: unsupported release (End of Life)

4. Distribution Details

The details on the distributions and versions of common dependencies and other considerations, see the official Target Platforms REP:

-  Target Platforms (REP 3) (<http://www.ros.org/reps/rep-0003.html>)

5. Release Schedule

Release rules

- ROS release timing is based on need and available resources
- All future ROS 1 releases are LTS, supported for five years
- ROS releases will drop support for EOL Ubuntu distributions, even if the ROS release is still supported.



Side effects of the release policy:

- Every ROS release will be supported on exactly one Ubuntu LTS.
- LTS releases will not share a common Ubuntu release with any previous releases.
- ROS releases will not add support for new Ubuntu distributions after their release date.

These simplified rules and side effects are subject to change with changes to the underlying Ubuntu release policy.

For more details see the official Release Policy (/Distributions/ReleasePolicy).

6. Upcoming releases

 Noetic Ninjemys is the final release of ROS 1 by Open Robotics (<https://www.openrobotics.org/blog/2020/5/23/noetic-ninjemys-the-last-official-ros-1-release>). Future ROS releases will all be based on ROS 2, and are  described on the [index.ros.org Releases](https://index.ros.org/doc/ros2/Releases/) page (<https://index.ros.org/doc/ros2/Releases/>).

7. Which distribution to use

A rather arbitrary list of usecase driven recommendations. *Updated* on May 2020.

New Capability	Major Update Frequency	Recommended distro
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Preferred but not required	Not preferred	Previous LTS (Melodic (/melodic))
Much preferred	Acceptable	Latest (Noetic (/noetic))
Much preferred	Not preferred	Switch to the latest LTS every 2 year

Specific platform is required	See REP-3 (http://www.ros.org/reps/rep-0003.html) for supported platform
Newer Gazebo is needed	Use Noetic (/noetic) for Gazebo 11
I want to use OpenCV3 (/opencv3)	Kinetic (/kinetic), Melodic (/melodic) or Noetic (/noetic)
I want to use OpenCV4 (/opencv4)	Noetic (/noetic)

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