**GPS : Ultimate GPS, Adafruit / Antenne VHBW**

<https://learn.adafruit.com/adafruit-ultimate-gps-on-the-raspberry-pi/using-uart-instead-of-usb>

**Python + Thread :**

<http://www.danmandle.com/blog/getting-gpsd-to-work-with-python/>

**Tuto ROS :**

<http://wiki.ros.org/gpsd_client/Tutorials/Writing%20a%20Subscriber%20for%20gpsd_client%20(C%2B%2B)>

**Centrale inertielle : imu01c, Pololu**

<https://github.com/DavidEGrayson/minimu9-ahrs/wiki>

(ou RTIMULib)

Plusieurs docs <https://www.pololu.com/product/2468>

Attention ! /dev/i2c-0 n’existe pas sur la Pi I. Utiliser /dev/i2c-1

**Spec télémètre Hokuyo**

<https://www.hokuyo-aut.jp/02sensor/07scanner/download/pdf/UTM-30LX-EW_spec_en.pdf>

**Tuto ROS télémètre**

<http://wiki.ros.org/hokuyo_node/Tutorials/UsingTheHokuyoNode>

**Brancher GPS en TTL**

<https://learn.adafruit.com/adafruit-ultimate-gps-on-the-raspberry-pi/using-uart-instead-of-usb>

<http://answers.ros.org/question/214630/navsat-robot_localization/>

**Télémètre LASER waterploof - 5300$**

<http://www.robotshop.com/en/hokuyo-utm-30lx-ew-laser-rangefinder.html>

**Echosondeur** micron tritech echosonder s06377

<http://www.tritech.co.uk/support-manuals/altimeter-manuals>