

ROS Toolbox のご紹介

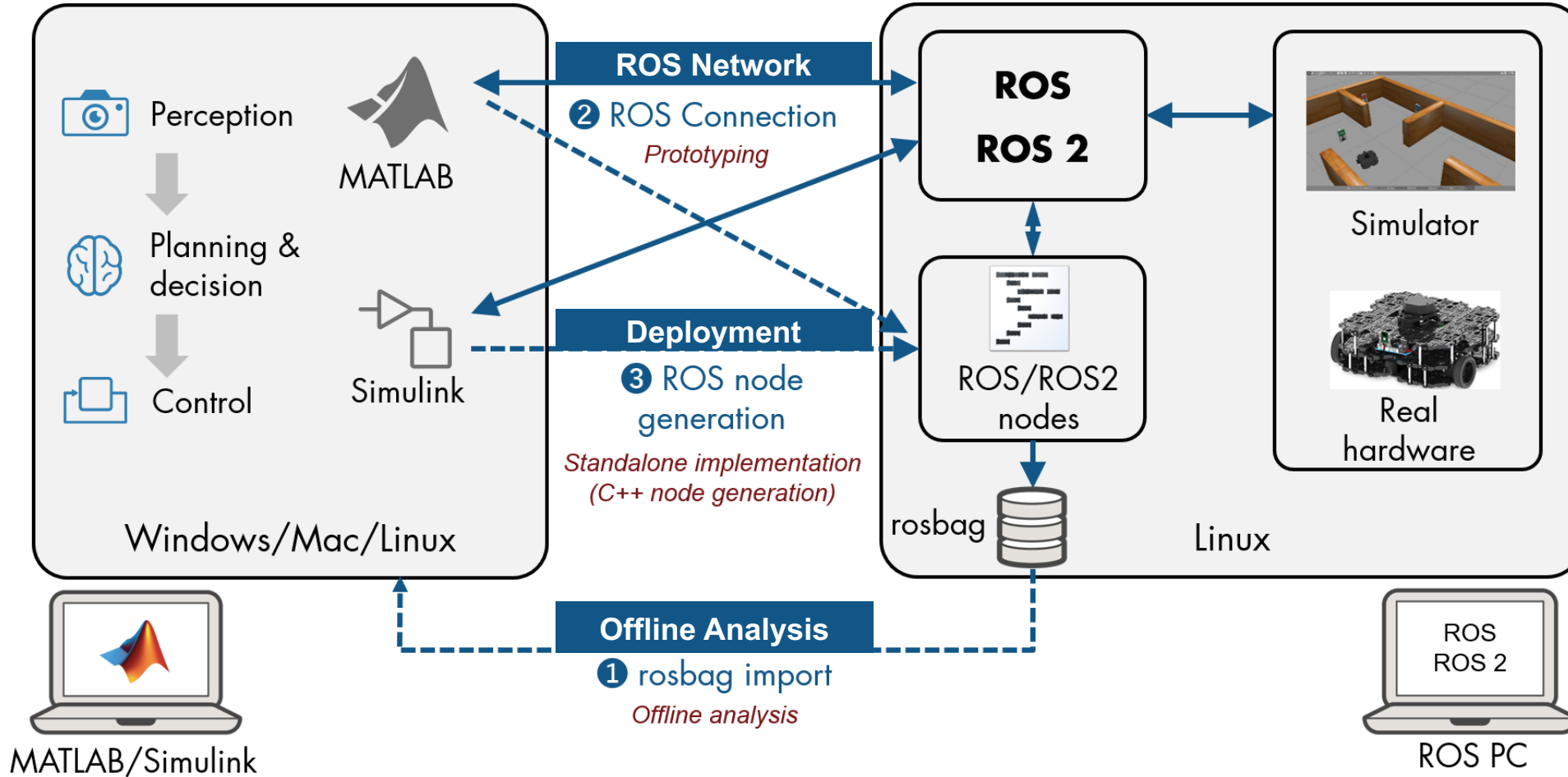


詳細はこちら

ROS Toolbox : MATLAB/SimulinkとROSを連携



詳細はこちら

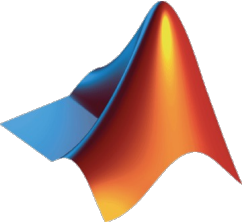
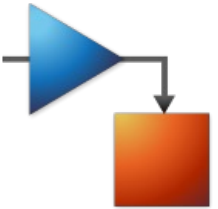


ROS Toolbox の主な対応機能

New in **R2022b**



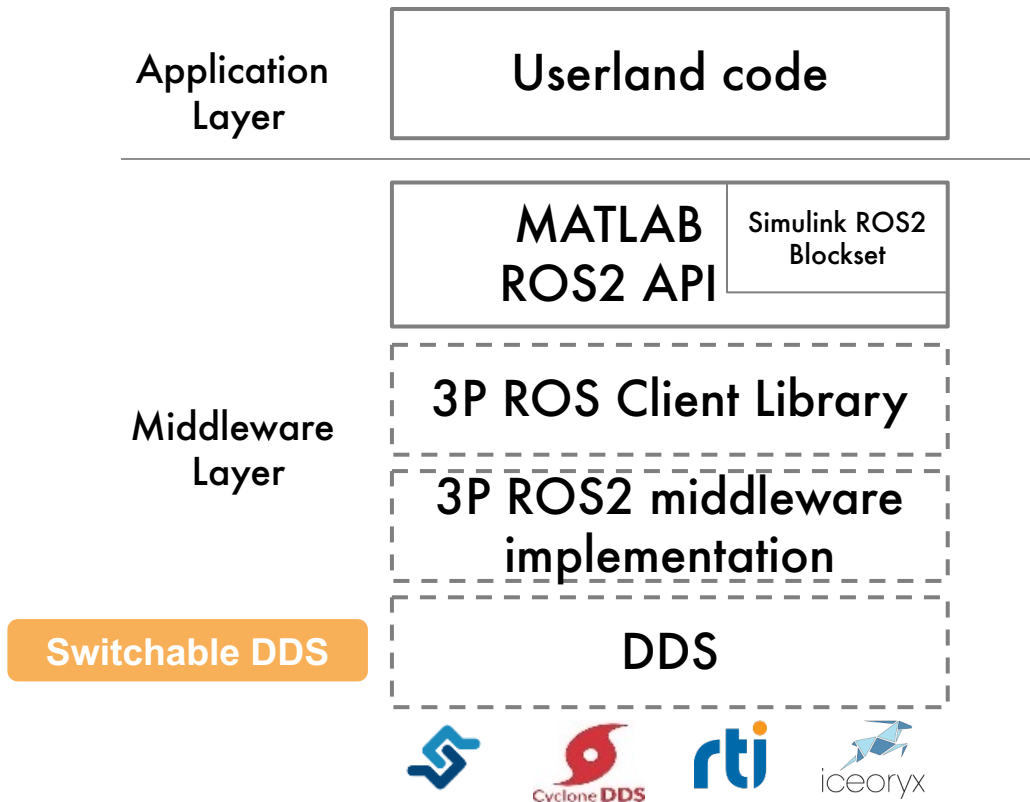
詳細はこちら

	ROS	2
	<ul style="list-style-type: none"> • Topic – Publish / Subscribe • Service server, Service client • Action – Client / Server • Parameter – Get / Set • ROS tf • Custom messages • rosbag read, rosbagwriter • Node generation • CUDA ROS node generation 	<ul style="list-style-type: none"> • Topic – Publish / Subscribe • Service server, Service client • Parameter – Get / Set • Custom messages • ros2bag read, ros2bagwriter • Node generation • CUDA ROS2 node generation
	<ul style="list-style-type: none"> • Topic – Publish / Subscribe • Service – Call • Parameter – Get / Set • ROS Time • rosbag playback / record • Code generation (Local/Remote) • CUDA ROS node generation 	<ul style="list-style-type: none"> • Topic – Publish / Subscribe • Service – Call • Parameter – Get • ROS2 Time • ros2bag playback • Code generation(Local/Remote) • CUDA ROS2 node generation
ROS Distro	<ul style="list-style-type: none"> • ROS Noetic 	<ul style="list-style-type: none"> • ROS2 Foxy Switchable DDS

異なるRMW実装の切り替え



詳細はこちら



**RMW Implementation = an interface between ROS2 and DDS

- Switch to the DDS of your choice
- You can choose “zero-copy communication” DDS

- Upgrade to **R2022b**
 - Fast DDS v2.2.0
 - Cyclone DDS v0.7.0
- Support other RMW implementations such as
 - RTI Connex DDS 6.0.1
 - Eclipse Iceoryx 1.0.2