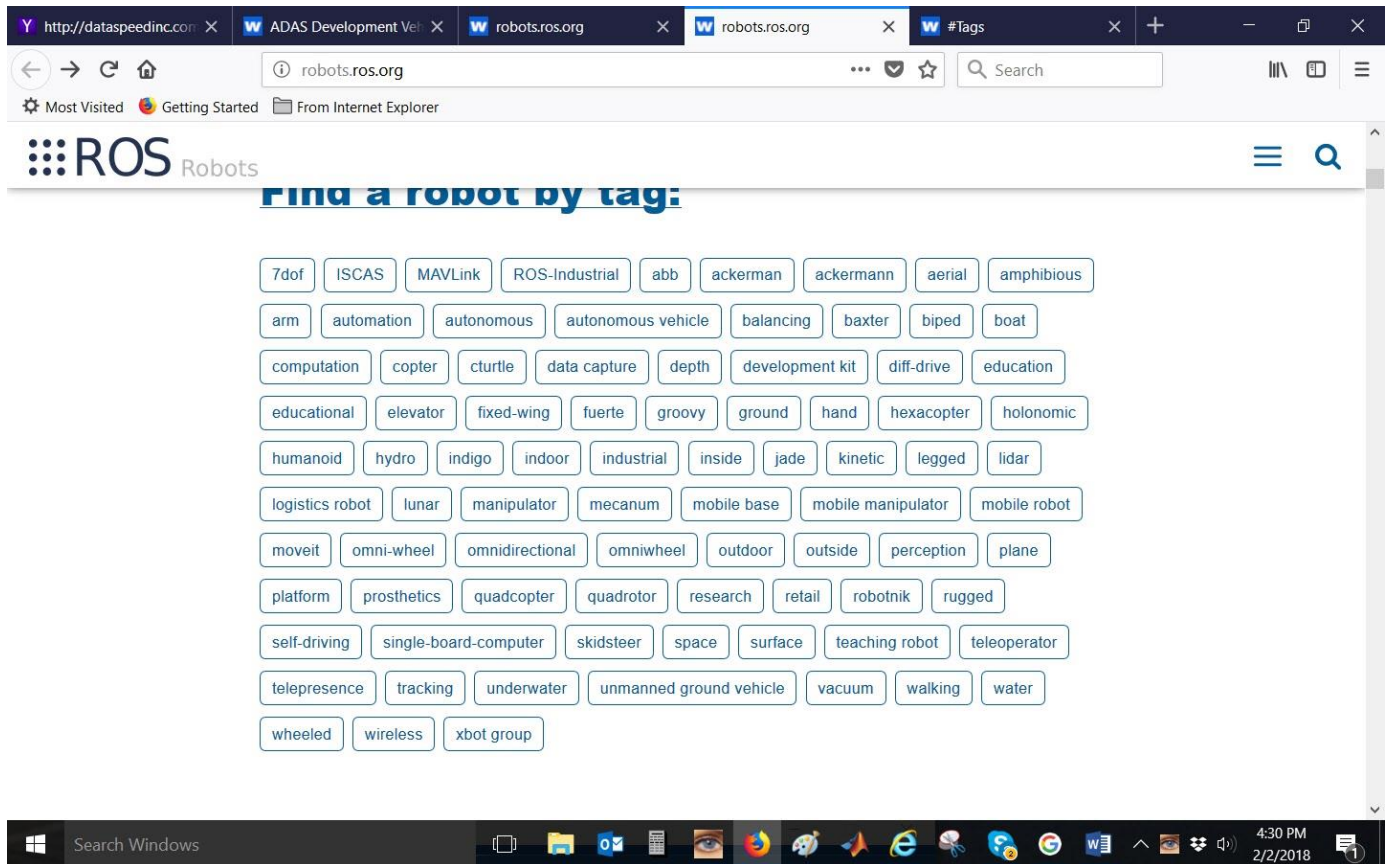


MOBILE ROBOTS USING ROS

<http://robots.ros.org/>



The screenshot shows a web browser window displaying the robots.ros.org website. The browser's address bar shows the URL robots.ros.org. The website's header includes the ROS logo and the text "ROS Robots". Below the header, there is a section titled "Find a robot by tag:" followed by a grid of 50 tags, each in a rounded rectangular button. The tags are arranged in 10 rows and 5 columns. The tags include: 7dof, ISCAS, MAVLink, ROS-Industrial, abb, ackerman, ackermann, aerial, amphibious, arm, automation, autonomous, autonomous vehicle, balancing, baxter, biped, boat, computation, copter, turtle, data capture, depth, development kit, diff-drive, education, educational, elevator, fixed-wing, fuerte, groovy, ground, hand, hexacopter, holonomic, humanoid, hydro, indigo, indoor, industrial, inside, jade, kinetic, legged, lidar, logistics robot, lunar, manipulator, mecanum, mobile base, mobile manipulator, mobile robot, moveit, omni-wheel, omnidirectional, omniwheel, outdoor, outside, perception, plane, platform, prosthetics, quadcopter, quadrotor, research, retail, robotnik, rugged, self-driving, single-board-computer, skidsteer, space, surface, teaching robot, teleoperator, telepresence, tracking, underwater, unmanned ground vehicle, vacuum, walking, water, wheeled, wireless, xbot group.

ADVANCED DRIVER ASSISTANCE SYSTEM

http://dataspeedinc.com/docs/ADAS_Kit.pdf



Carla is a self-driving [Lincoln MKZ](#) developed by Udacity and equipped with LIDAR, [radar](#), and cameras.

<http://robots.ros.org/category/marine/>

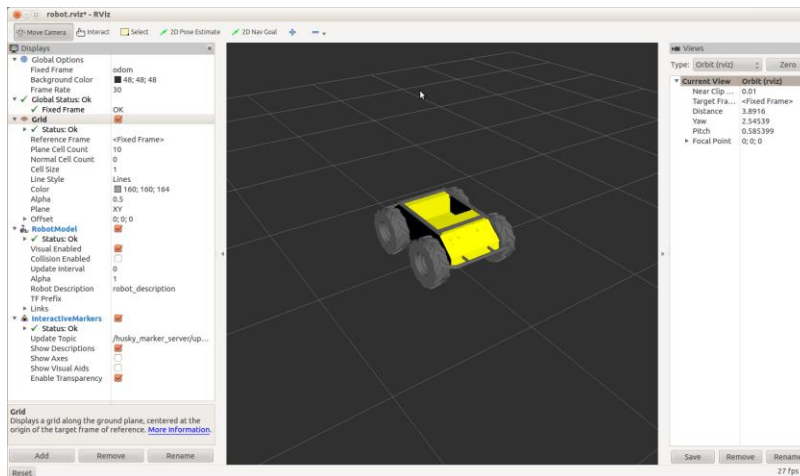
REFERENCE FOR SELF-DRIVING CARS USING ROS:

ROS Robotics Projects Lentil Joseph Chapter 10, Packt Publishers, 2017



SIMULATORS

<http://www.clearpathrobotics.com/assets/guides/ros/Drive%20a%20Husky.html>



HUSKY



ROBONAUT

Erle-Plane



Sensors supported by ROS

<http://wiki.ros.org/Sensors>

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[Sensor Interfaces](#) EXAMPLE LASER SCANNER

- [hokuyo_node](#)
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1. [How to use Hokuyo Laser Scanners with the hokuyo_node](#)

This tutorial is an introduction to using a Hokuyo laser scanner connected to a desktop. After reading this tutorial, you should be able to bring up the hokuyo_node and display the laser [data](#).

2. [How to Dynamically Reconfigure the hokuyo_node](#)

This tutorial covers using the reconfigure_gui to dynamically reconfigure the hokuyo_node to run with different parameters. After reading this tutorial, you should be able to bring up the reconfigure_gui and change the hokuyo_node parameters.

3. [How to dynamically reconfigure the hokuyo_node from the command line or code.](#)

After completing this tutorial, you will be able to reconfigure the parameters of the hokuyo_node from the command line or python [code](#)