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## ROS DISTRIBUTIONS

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

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.

# List of Distributions For ROS 1

Distro	Release date	Poster	Tuturtle, turtle in tutorial	EOL date
ROS Noetic Ninjemys (Recommended)	May 23rd, 2020			May, 2025 (Focal EOL)
ROS Melodic Morenia	May 23rd, 2018			May, 2023 (Bionic EOL)
ROS Lunar Loggerhead	May 23rd, 2017			May, 2019
ROS Kinetic Kame	May 23rd, 2016			April, 2021 (Xenial EOL)
ROS Jade Turtle	May 23rd, 2015			May, 2017
ROS Indigo Igloo	July 22nd, 2014			April, 2019 (Trusty EOL)
ROS Hydro Medusa	September 4th, 2013			May, 2015
ROS Groovy Galapagos	December 31, 2012			July, 2014

## List of Recent Distributions For ROS 2

<https://docs.ros.org/en/rolling/Releases.html>

Distro	Release date	Logo	EOL date
Humble Hawksbill	May 23rd, 2022		May 2027
Galactic Geochelone	May 23rd, 2021		November 2022
Foxy Fitzroy	June 5th, 2020		May 2023

### DISTRIBUTION AND MAJOR OS SUPPORT ROS1:

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



ROS Kinetic Kame is the tenth [ROS distribution release](#). It was released May 23rd, 2016. Ubuntu Xenial (16.04 LTS)

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



ROS Melodic Morenia is the twelfth [ROS distribution release](#). It was released on May 23rd, 2018. Bionic (18.04 LTS)

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

ROS Noetic Ninjemys is the thirteenth [ROS distribution release](#). It was released on May 23rd, 2020.



**PROBLEM:** With latest versions  
– your packages may not work! However, most changes are “in the engine room” and do not invalidate your code.

e.g. `command_velocity` (Goovy) became `cmd_vel`  
Our Baxter uses Groovy. Turtlebot uses Kame.

## ROS AND UBUNTU DISTRIBUTIONS

ROS is not strictly tied to Ubuntu-based operating systems; however, Ubuntu is the primarily supported operating system for ROS. "LTS" (long term support) distributions of ROS are synchronized with the LTS distributions of Ubuntu. To maximize compatibility, the distribution of ROS you install should match the version of Ubuntu you are running based on this list. ROS distributions are listed.

- Ubuntu 14.04.06 LTS (Trusty Tahr) --> ROS Indigo Igloo
- Ubuntu 16.04.7 LTS (Xenial Xerus) --> ROS Kinetic Kame
- Ubuntu 18.04.5 LTS (Bionic Beaver) --> ROS Melodic Morenia
- Ubuntu 20.04.1 LTS (Focal Fossa) --> ROS Noetic Ninjemys, ROS2 Foxy
- Ubuntu 22.04 LTS LTS Jammy Jellyfish → (ROS2)

## UBUNTU Flavors

<https://ubuntu.com/desktop/flavours>

Ubuntu flavours offer a unique way to experience Ubuntu, each with their own choice of default applications and settings. Ubuntu flavours are owned and developed by members of our global community and backed by the full Ubuntu archive for packages and updates.

Ubuntu MATE, **Kubuntu**, etc.