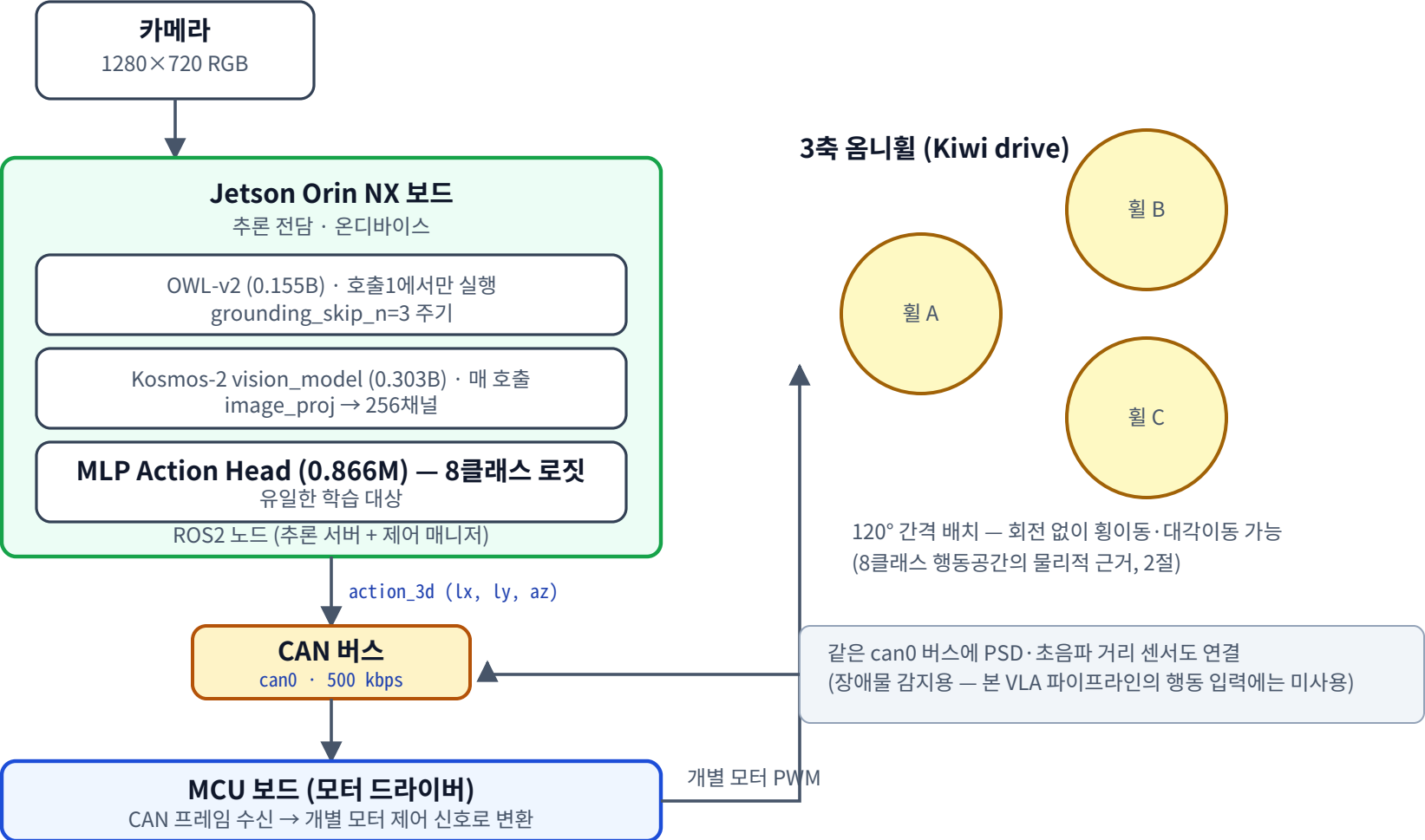


하드웨어 구성 — Jetson ↔ CAN ↔ MCU



근거: ROS_action/.../omni_controller/omni_drive_node.py — Psd/Ultrasonic(dev="can0", bitrate=500000), robov1m_nav/serve/vla_control_utils.py — pop.driving.Driving()