# Article information:

ROS2--DDS - 知乎  
<https://zhuanlan.zhihu.com/p/59465983>

# Article summary:

1. ROS2 is built on the DDS program, which is used to discover nodes, serialize and transfer messages.

2. Different companies may offer different implementations of DDS to suit different scenarios. Fast RTPS is an open source library that can be used for ROS2 message publishing/subscribing.

3. Fast Buffers is a serialization library that can be used to store objects, send them over networks, and restore them from byte arrays.

# Article rating:

Appears well balanced: The article presents the information in a reliable and balanced way, without biases and prejudices. The claims made in the article are well supported and, where applicable, all sides of the argument are given opportunity to present their point of view. The article appears trustworthy and reliable.

# Article analysis:

The article provides a comprehensive overview of the use of DDS in ROS2 and the features of Fast RTPS and Fast Buffers libraries. The article does not appear to have any biases or one-sided reporting, as it presents both sides of the argument equally and objectively. It also provides evidence for its claims by citing examples such as RTI's Connext implementation and eProsima's Fast RTPS implementation. The article does not appear to have any missing points of consideration or missing evidence for its claims, as it covers all relevant topics in detail. Furthermore, there are no unexplored counterarguments or promotional content present in the article.

The only potential issue with the article is that it does not mention any possible risks associated with using these libraries in ROS2 applications, such as security risks or performance issues. However, this does not detract from the overall trustworthiness and reliability of the article itself.

# Topics for further research:

* ROS2 DDS security risks
* Performance issues with Fast RTPS
* Advantages of using Fast Buffers
* Limitations of using Connext in ROS2
* Comparison of Fast RTPS and Connext
* Best practices for using DDS in ROS2

# Report location:

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