

ROSCon FR&DE 2025

WORKSHOPS

Workshop Title	Building Real-Time Robotic Systems with QNX and ROS2
Name of principal instructor	Erik Johnson (QNX)
Number of supplementary instructors	4
Maximum of participants	30
Language	English
Workshop duration	2h
Required material	Each participant should have a laptop with a USB port.
Skills required for participants	Beginners

Brief description	QNX is a real-time operating system (RTOS) engineered for deterministic behaviour, fault isolation, and high reliability - properties essential for safety-critical applications in automotive, medical, and industrial domains. QNX is a POSIX-compliant microkernel RTOS that can provide hard real-time scheduling and a clear path towards safety certification making it ideal for building robotic systems. This workshop presents a practical workflow to deploying ROS2 on QNX through freely available development tools and a pre-configured Raspberry Pi image. It will also show how the wide array of powerful ROS2 packages can be cross-compiled for and used on QNX. Potential issues and best practices for using ROS2 on QNX will be discussed throughout. This workshop will provide a general introduction to the QNX RTOS, including relevant design features like its microkernel and POSIX nature. It will show participants how to access QNX development tools and the Raspberry Pi image. Then it will demonstrate the process of cross-compiling ROS2 for QNX. The participants will go hands-on to explore the command line of a running QNX Raspberry Pi and learn useful commands for introspection of the system (e.g. <code>pidin</code>, <code>slog2info</code>). They will run example ROS2 nodes that illustrate the real-time nature of QNX. Finally an example will be given of cross-compiling a complex ROS2 package on QNX : <code>ros2_control</code>. Throughout the workshop, potential issues and best practices specific to using ROS2 on QNX will be highlighted. Raspberry Pi will be available for participants to experiment on during the workshop.
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