

## PID & Foxy 启动流程

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1. `cd /carla-ros-bridge`
2. `source source_env.sh`
3. `colcon build`
4. `source source_env.sh`
5. `ros2 launch carla_shenlan_bridge_ego_vis carla_bridge_ego_vehicle.launch.py`
6. 在新的终端里面: `ros2 run carla_shenlan_pid_controller carla_shenlan_pid_controller_node`

## Stanley & Foxy 启动流程

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1. `cd /carla-ros-bridge`
2. `source source_env.sh`
3. `colcon build`
4. `source source_env.sh`
5. `ros2 launch carla_shenlan_bridge_ego_vis carla_bridge_ego_vehicle.launch.py`
6. 在新的终端里面: `ros2 run carla_shenlan_stanley_pid_controller carla_shenlan_stanley_pid_controller_node`