

carla 里面方向盘左正右负

PID & Foxy 启动流程

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_vehilce.launch.py`
6. 在新的终端里面: `ros2 run carla_shenlan_pid_controller carla_shenlan_pid_controller_node`

Stanley & Foxy 需要完成的内容

1. `src/ros-bridge/carla_shenlan_projects/carla_shenlan_stanley_pid_controller/src/stanley_controller.cpp` 中的 TODO 部分

Stanley & Foxy 启动流程

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_vehilce.launch.py`
6. 在新的终端里面: `ros2 run carla_shenlan_stanley_pid_controller carla_shenlan_stanley_pid_controller_node`

LQR & Foxy 需要完成的内容

1. `carla-ros-bridge/src/ros-bridge/carla_shenlan_projects/carla_shenlan_lqr_pid_controller/src/lqr_controller.cpp` 中的 TODO 部分

LQR & Foxy 启动流程

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_vehilce.launch.py`
6. 在新的终端里面: `ros2 launch carla_shenlan_lqr_pid_controller lqr_launch.py`

MPC & Foxy 需要完成的内容

1.

MPC & Foxy 启动流程

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_vehilce.launch.py`
6. 在新的终端里面: `ros2 launch carla_shenlan_mpc_controller mpc_launch.py`

Lattice & Foxy 启动流程

1. 需要完成部分： `lattice_planner.cpp` 中的TODO部分
2. `cd /carla-ros-bridge`
3. `source source_env.sh`
4. `colcon build`
5. `source source_env.sh`
6. `ros2 launch carla_shenlan_bridge_ego_vis carla_bridge_ego_vehilce.launch.py`
7. 在新的终端里面: `ros2 launch carla_shenlan_lattice_planner lattice_launch.py`