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