

[Last update: January 11, 2022]

### Pre-requisites:

- Ubuntu 20.04
- Python 3.8
- CARLA 0.9.11: <https://github.com/carla-simulator/carla/releases/tag/0.9.11>
  - [Ubuntu] [CARLA\\_0.9.11.tar.gz](#)
- ROS: <http://wiki.ros.org/noetic/Installation/Ubuntu>

### Instructions:

1. Install individual repositories (each repo has its own instruction)
  - \*\* NOTE: install carla-setup at last
  - \*\* NOTE: instruction on setting CARLA included in carla-setup
    - [honda-research-institute/decision-governor \(github.com\)](#) branch: master
    - [honda-research-institute/nnmpc \(github.com\)](#) branch: 0.9.11
    - [honda-research-institute/external\\_lib\\_AI4AD \(github.com\)](#) branch: 0.9.11
    - [honda-research-institute/Interactive\\_Decision\\_Making\\_v2.0: Game Tree method turned modular for the T intersection \(github.com\)](#) branch: master
    - [honda-research-institute/mpqp\\_speed\\_planner \(github.com\)](#) branch: devel
    - [honda-research-institute/gatekeeper \(github.com\)](#) branch: master
    - [honda-research-institute/spiral\\_planner \(github.com\)](#) branch: master
    - [honda-research-institute/escape\\_safety \(github.com\)](#) branch: master
    - <https://github.com/honda-research-institute/traffic-rule-stop-predictor> branch: master
    - [https://github.com/honda-research-institute/scenario\\_runner](https://github.com/honda-research-institute/scenario_runner) branch: 0.9.11 (or 0.9.11-ss-4way)
    - [honda-research-institute/carla-setup: Set up the testing scenario in Carla simulator. \(github.com\)](#) branch: 0.9.11

### To run:

1. In the terminal: \$ roslaunch demo\_entrance scneario\_loader\_4way\_intersection.launch
2. In new terminal: \$ roslaunch demo\_entrance run\_full\_system.launch
3. In new terminal: \$ python ~/scenario\_runner/scenario\_runner.py --scenario HRI4WayIntersection\_4 --waitForEgo --repetitions 10