Which nodes can I make them work on?

Step 1: Joy-mapper → car_cmd (publish Control)

⇒ allow them to get familiar with ROS topics
⇒ first, understand how does the joystick command work.

Step 2: Inverse-kinematics → translate car_cmd
into msg_wheels_cmd.
(car_cmd_callback)

⇒ understand how the ~~control works joystick information~~
command is turned into ~~desired you~~ wheel power
⇒ introduction to parameters of ROS

Step 3: Line detector → pub_lines (segment list)
⇒ 1) detector line_detector 1
~~rewritten~~
⇒ jump into a bit of computer vision

Step 4: Lane filter node lane_filter.py
⇒ filter predict
⇒ filter update

⇒ State estimation

Step 5: Lane_controller_node, cbPose

⇒ Control