Make sure the map has been generated by Hector SLAM or cartographer before running pure pursuit (Follow particle filter before below steps for localization and waypoints)

1. Get maps under lab\_pure\_pursuit folder
2. Make sure the map\_file argument in pure\_pursuit.launch file is updated with the correct path to map file generated from cartographer.
3. Check the pure\_pursuit.py file and search for the argument which calls the waypoint csv file make sure it is the same csv that corresponds to map otherwise the car won’t be able to traverse correctly.
4. Go to f110 workspace: cd f110\_ws/
5. Run: source devel/setup.bash
6. Run: roslaunch lab\_pure\_pursuit pure\_pursuit.launch.
7. Press ‘W’ key to start the car and spacebar to stop the car.