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

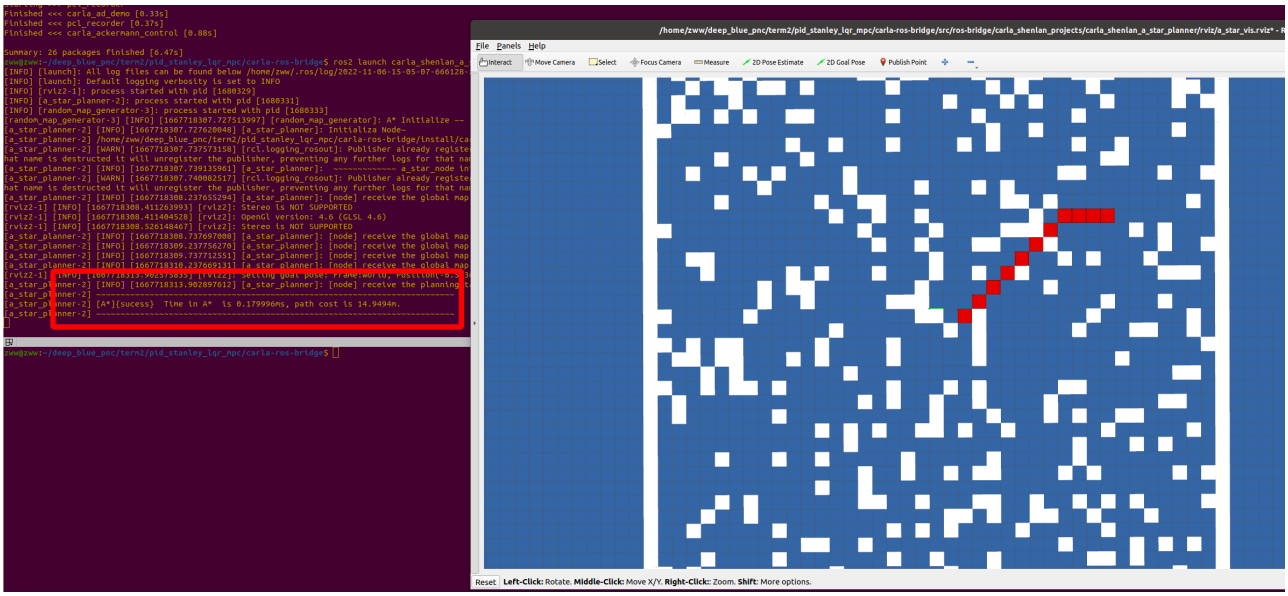
1. cd /carla-ros-bridge
2. source source_env.sh
3. colcon build
4. source source_env.sh
5. ros2 launch carla_shenlan_bridge_ego_vis carla_bridge_ego_vehilce.launch.py
6. 在新的终端里面: ros2 launch carla_shenlan_lattice_planner lattice_launch.py

A* & 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_a_star_planner a_star_planner.launch.py

作业要求

1. carla-ros-bridge/src/ros-bridge/carla_shenlan_projects/carla_shenlan_a_star_planner/src/Astar_searcher.cpp 中的 TODO部分
2. 对比分析不同的启发函数的计算耗时，每次运行后在终端内会打印计算时间，需要截图放入文档中上传。


Finished <<< carla_ad_demo [0.33s]
Finished <<< pcl_recorder [0.37s]
Finished <<< carla_ackermann_control [0.88s]
Summary: 26 packages finished [6.47s]
[INFO] [launch]: All log files can be found below /home/zww/.ros/log/2022-11-06-15-05-07-666128-
[INFO] [launch]: Default logging verbosity is set to INFO
[INFO] [rviz2-1]: process started with pid [1680329]
[INFO] [a_star_planner-2]: process started with pid [1680331]
[INFO] [random_map_generator-3]: process started with pid [1680333]
[a_star_planner-2] [INFO] [1667718307.739135961] [a_star_planner]: ~~~~~~~~~~ a_star_node in
[rviz2-1] [INFO] [1667718308.411263993] [rviz2]: Stereo is NOT SUPPORTED
[rviz2-1] [INFO] [1667718308.411404528] [rviz2]: OpenGl version: 4.6 (GLSL 4.6)
[rviz2-1] [INFO] [1667718308.526148467] [rviz2]: Stereo is NOT SUPPORTED
[a_star_planner-2] [INFO] [1667718308.737697088] [a_star_planner]: [node] receive the global map
[a_star_planner-2] [INFO] [1667718309.237756270] [a_star_planner]: [node] receive the global map
[a_star_planner-2] [INFO] [1667718309.737712551] [a_star_planner]: [node] receive the global map
[a_star_planner-2] [INFO] [1667718310.237669131] [a_star_planner]: [node] receive the global map
[a_star_planner-2] [INFO] [1667718313.902897612] [a_star_planner]: [node] receive the planning t
[a_star_planner-2] ~~~~~~
[a_star_planner-2] [A*](sucess) Time in A* is 0.179996ns, path cost is 14.9494m.
[a_star_planner-2] ~~~~~~
/home/zww/deep_blue_pnc/term2/pid_stanley_lqr_mpc/carla-ros-bridge/src/ros-bridge/carla_shenlan_projects/carla_shenlan_a_star_planner/rviz/a_star_vis.rviz* - R
File Panels Help
Interact
Move Camera
Select
Focus Camera
Measure
2D Pose Estimate
2D Goal Pose
Publish Point
Reset
Left-Click: Rotate. Middle-Click: Move X/Y. Right-Click: Zoom. Shift: More options.