

System startup guide

1. Turn on the motion platform rig by turning on the red **switch** so that the green light turns on.



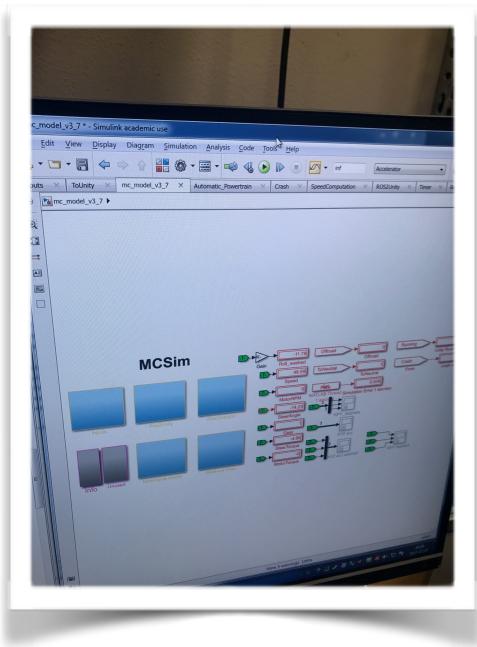
2. On the motion PC, make sure to set the Mode Of operation of HyPCoS UUclient to “**Normal mode**” and to **acknowledge** all errors in the Error Handler window.

3. Log in to the **Raspberry Pi** with password *New4you*. Start **ROS** communication by typing in these two commands in the bash:

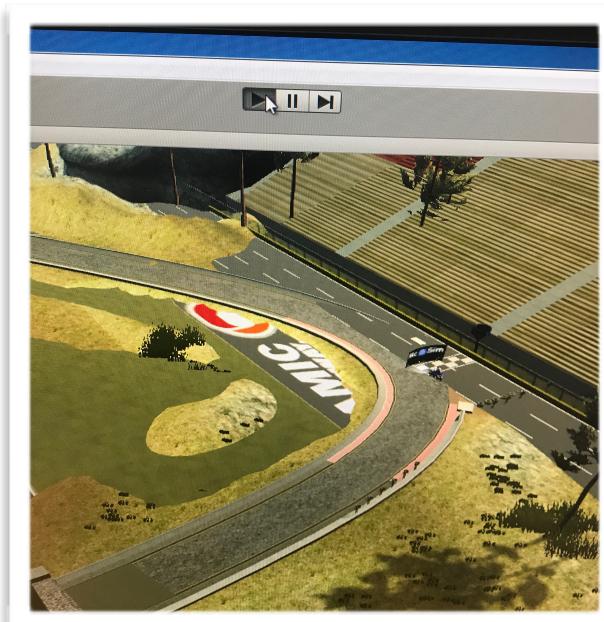
```
> roslaunch master system.launch  
> rosrun rosserial_python serial_node.py _port:=/dev/ttyACM1  
_baud:=115200 __name:=Arduino_SUB
```

4. Open the Matlab script **runModel.m** and run the code.

5. Open the Simulink model **mc_model_v3_7**.



6. **Run** the model by pressing the green “play button”.
7. **Open** the **Unity3D** application and open the project folder “**MCsim**”, (scene: *race_track_lane*). Make sure that the VR - headset is connected though USB and HDMI.
8. **Run** the simulator-game by clicking the “play button”.



9. Now that ROS, Simulink, Unity and the rig is running, the user should be able to start the Simulator with the VR Headset by looking at the button **“Start Simulator”** and turn on the Rig motion by switching on the **red switch** on the **right** side of the handlebar.