
apollo-carla-bridge Documentation

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1.1 Installation

1.1.1 Apollo side

1. Clone the repos **Recommended**

- Clone and install apollo from the [official repo](#)
- Clone the folder ws_apollo_carla_bridge from [nemodrive/apollo](#) repo (see [sparse checkout](#))
- Copy the cloned directory to the apollo folder

Alternative

- Clone the whole [nemodrive/apollo](#) repo and install apollo from there (it is probably behind the official repo)

2. Install (do this in apollo docker)

```
cd ws_apollo_carla_bridge
catkin_make
```

1.1.2 Carla side

- Clone [nemodrive/carla](#)
- Create a catkin workspace anywhere
- In -s \${carla_root}/carla-ros-bridge \${catkin_workspace}/src/carla-ros-bridge
- cd \${catkin_workspace}
- catkin_make

1.2 Config

Most setup is to be done on carla's side of the bridge, in the file `${carla-ros-bridge}/conf/settings.yaml`. Modify this file to add / remove sensors.

Camera image and information will be published on topics with the following format:

- `${camera_name}/image_raw` -> `sensor_msgs/Image`
- `${camera_name}/camera_info` -> `sensor_msgs/CameraInfo` (camera's intrinsic parameters)

Vehicle information is published on `/player_vehicle`. Carla listens to control on `/carla_control`.

1.3 Running

To run the bridge do everything in the order specified!!! Run the apollo part first:

```
dev_Start && dev_into && bootstrap.sh + modules: localization, perception, planning, \
↳routing, prediction, control
(in docker) cd ws_apollo_carla_bridge
(in docker) source devel/setup.bash
(in docker) rosrun apollo_carla_bridge bridge.py
```

Now run the carla part:

```
start carla
cd ${carla_ros_bridge_ws}
source devel/setup.bash
roslaunch carla_ros_bridge client.launch
```

If you've done everything correctly, you should see the car in dreamview. :)

CHAPTER 2

Indices and tables

- `genindex`
- `modindex`
- `search`