CARLA Cheat Sheet - manual control

CARLA (`http://carla.org/`) is a simulation environment aimed at self-driving cars. This cheat sheet covers basic options for a first exploration using the manual control environment.

Start simulation

```
CarlaUE4.sh <parameter list>
```

using docker
default settings (Town03):

```
docker run -p 2000:2002:2000-2002 \
--runtime-nvidia \
-e NVIDIA_VISIBLE_DEVICES=0 \
carlasim/carla
```

with custom settings: add

```
/bin/bash CarlaUE4.sh <parameter list> --world-port='2000'
```

to the command above (e.g. Town07 as parameter)

Control

Key	Action
W, ↑	throttle
A, ←	steer left
D, →	steer right
S, ↓	brake
Q	toggle reverse
Space	handbrake
M	toggle manual transmission
,/.	gear up/down
P	toggle autopilot

GUI

Key	Action
TAB	toggle view (change camera position)
F1	toggle hud
H/?	toggle help
ESC	quit

Misc

Key	Action
BACKSPACE	change car/motor cycle/whatever model
C	change weather

Recording

Key	Action
R	toggle recording images to disk
CRTL + R	toggle recording of simulation
CRTL + P	toggle replay of last recorded simulation
CRTL + +	increment start frame of replay
CRTL + -	decrement start frame of replay

Sensors

Key	Action
1	switch to RGB camera
2	switch to depth camera (raw)
3	switch to depth camera (gray scale)
4	switch to depth camera (log gray scale)
5	switch to semantic segmentation (raw = black screen)
6	switch to semantic segmentation (city scapes colormap)
7	switch to LiDAR view
8	switch to RGB camera
9	switch to depth camera (raw)