第八章作业 Lanelets 裁剪

第八章作业是利用几何知识点对 Lanelet 进行起点和终点的裁剪，主要参考以下文章

[(108 条消息) 面向自动驾驶的高精度地图框架解析和实战_智能交通技术的博客-CSDN 博客](#)
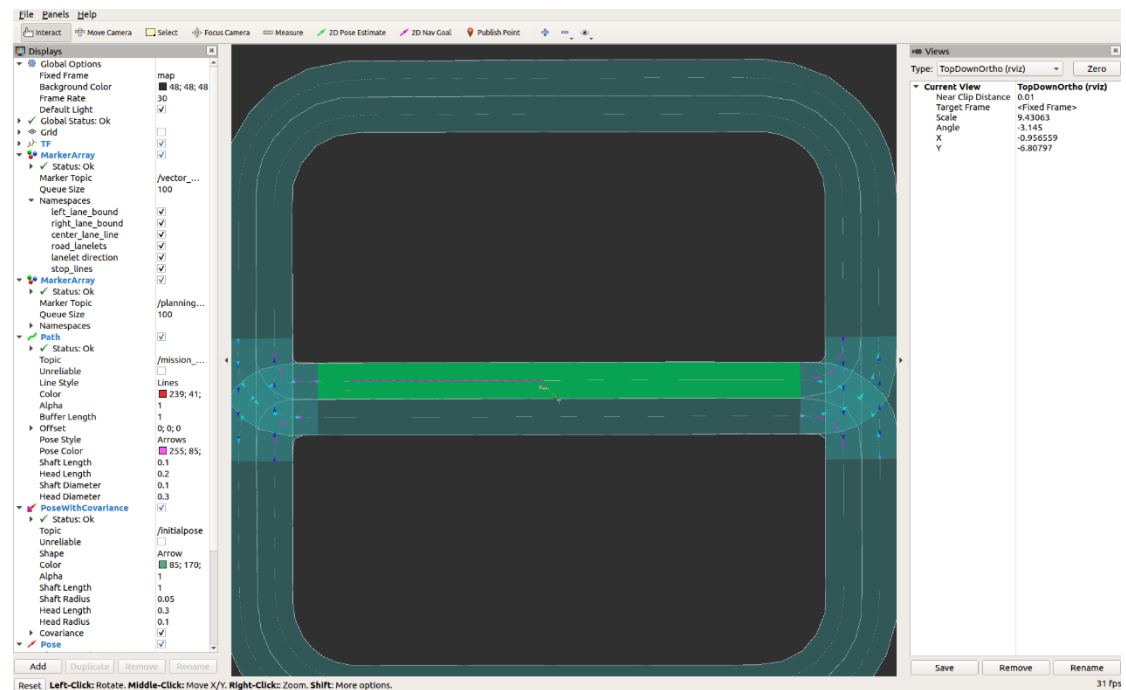
参考的 Github 有以下两个
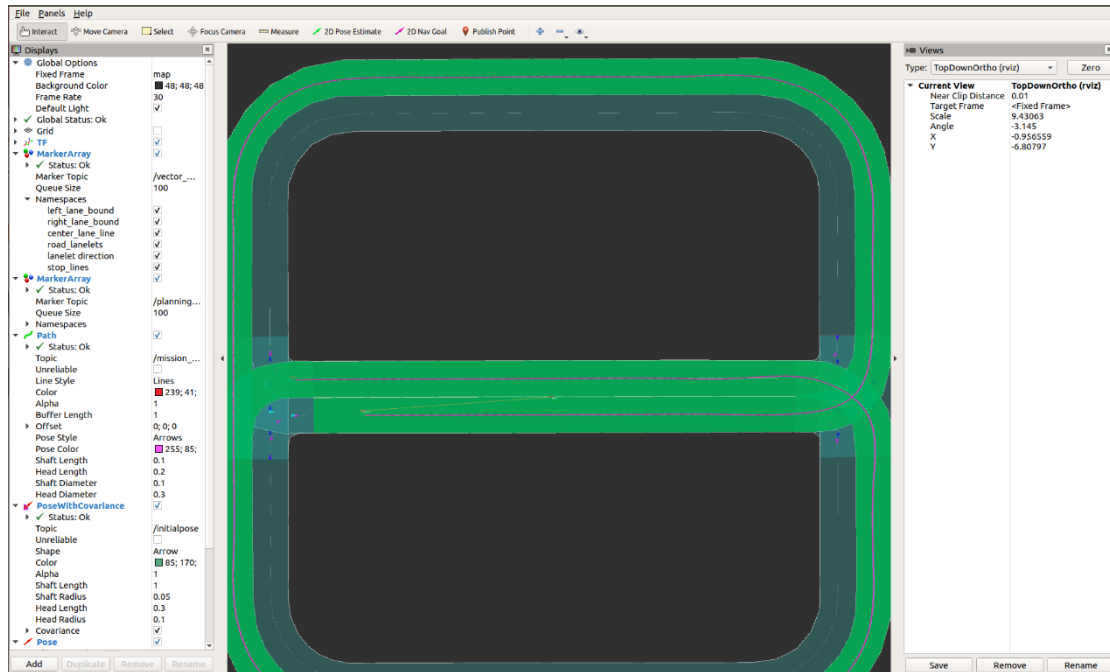
https://github.com/fzi-forschungszentrum-informatik/Lanelet2

https://github.com/AbangLZU/ad_with_lanelet2

另外如果你要使用五次曲线拟合最终生成的路径，可以使用第 6 章作业中的一些曲线拟合的库，需要将相应的头文件复制到本章的 src 文件夹下面。

编写完成之后按照作业指导的要求运行代码，会出现以下的效果

src/run_map_simulator.launch http://localhost:11311

File Edit View Search Terminal Help

```
ROS_MASTER_URI=http://localhost:11311

setting /run_id to c3711e86-2a8f-11ed-85e0-0068ebb66580
process[rosout-1]: started with pid [25601]
started core service [/rosout]
process[simple_planning_simulator-2]: started with pid [25610]
process[relay-3]: started with pid [25619]
process[lanelet2_map_loader-4]: started with pid [25620]
process[lanelet2_map_visualization-5]: started with pid [25628]
process[hd_map-6]: started with pid [25644]
process[mission_planner-7]: started with pid [25659]
process[rviz-8]: started with pid [25675]
[ INFO] [1662103247.298788082]: vehicle_model_type = DELAY_STEER_ACC
[ INFO] [1662103247.306710010]: initialize_source : RVIZ
[ INFO] [1662103250.323674730]: [simple_planning_simulator] waiting initial posi
tion...
[ INFO] [1662103255.778994283]: New goal pose is set. Reset checkpoints.
[ INFO] [1662103255.782060420]: start planning route with checkpoints:
x: 33.4334 y: 2.3462
x: 45.711 y: -3.62691

lanelet_size is 8
[ INFO] [1662103255.801627949]: Route successfuly planned. Publishing...
```