连接vpn ：sudo openvpn --config {path to 个人配置文件}

g++ -g -Wall -std=c++11 main.cpp

python39 -m pip install 库名

dpkg -L ros-kinetic-autowise-protobuf3

/aw/planning/raw\_robot\_trajectory\_marker

节点路径：/opt/ros/kinetic/lib/aw\_simulation\_obstacle（修改obstacle\_restorer.cpp ProcessDoingCreateDynamicObstacle方法的时间相关（有注释）的代码后， 在aw\_simulation\_obstacle\_new文件夹内cmake. make在此加入新的obstacle\_restorer\_node覆盖原来的，在aw\_test\_newer里测试 \*\*旧的节点文件在qyc/backup里有）\*\*\*从JIADING-E6开始可以playcase

Ls的时候列出当前目录的文件、文件夹完整路径

ls -1 |awk '{print i$0}' i=`pwd`'/'

查看一级目录下面哪个文件夹占用最多空间：du -h --max-depth=1

删除七天前的文件：find . -type f -mtime +7 -exec rm -f {} \;

（删除七天内的是-7）

Hadoop autowise@shhq-data00:~/hadoop-3.1.1/bin$ ./hadoop fs -ls -h /bag\_data/regression\_bag/20200921

（在本机上可以直接hadoop fs -ls h ...）

./hadoop fs -rm /bag\_data/regression\_bag/regression\_test.sh

./hadoop fs -put /home/autowise/qyc/regression\_test.sh /bag\_data/regression\_bag

sudo service sync\_bag\_to\_plugged\_device restart

sudo journalctl -f -u sync\_bag\_to\_plugged\_device.service

bash install\_sync\_bag\_to\_plugged\_device.sh

ps -ef | grep roscore

rosrun rqt\_graph rqt\_graph

update\_autowise\_debs\_and\_models.sh -l

可视化

roslaunch aw\_visualization planning\_vis.launch

rviz -d /opt/ros/kinetic/share/aw\_visualization/rviz/planning.rviz

rosrun aw\_bag play /data/de\_wilhelmshaven/20190611/2019\_06\_11\_00\_20\_07\_arts16\_4 -s 6540 -u 180

文件管理器卡住：ps -A | grep nautilus kill

删除指定后缀的文件find . -name "\*.active" | xargs rm -rf

grep搜索当前目录：grep -r "待查找内容" ./

复制指定前缀文件到指定目录：

find /home/autowise/bags/regression\_bags/ -type f -name "2020\_08\_05\_10\_00\_43\*" -exec cp -b {} /home/autowise/data/ ";"

对目录中每个文件创建一个todo文件：

for file in `ls ~/data/regression\_bags/20200806/`; do touch ${file}.todo; done

rosrun aw\_bag search project=pheonix\_walmart

rosrun aw\_bag search path="%2020\_04\_07\_05\_25\_30\_buss2\_1\_pheonix\_walmart\_0%"

rosrun aw\_bag play /data/pheonix\_walmart/20200723/2020\_07\_23\_20\_11\_23\_buss2\_1\_pheonix\_walmart\_1 -s 215 -u 70 -f --topics /aw/planning\_info /aw\_cam00\_rep/image\_raw/compressed

rosrun aw\_bag play --help

topic : /aw/planning\_info /aw\_cam00\_rep/image\_raw/compressed /aw\_cam00/image\_raw/compressed

Task 目录

/opt/ros/kinetic/share/aw\_launch/config/conf/tasks/

HDMAP launch目录

/opt/ros/kinetic/share/aw\_hdmap/launch

source ~/.autowise/setup.sh

rosrun aw\_launch aw\_config.py --cfg arts16 beijing\_chaoyang

roslaunch aw\_hdmap hdmap\_chaoyang\_park.launch

export PLANNING\_TASK=/opt/ros/kinetic/share/aw\_launch/config/conf/tasks/pheonix\_walmart/pheonix\_walmart\_night2.yaml

source ./devel/setup.sh

roslaunch aw\_global\_planning route\_points\_generator.launch

cd ~ cd workspace/ cd ccpp/ cd autowise\_global\_planning/ source ./devel/setup.sh

## Docker相关

docker image ls

docker image prune 清理无用image

docker run -ti --rm registry.autowise.ai/awcar

docker run -ti --rm -e "TERM=xterm-256color" "$@" -e "DISPLAY=:0" -e "QT\_X11\_NO\_MITSHM=1" -v /tmp/.X11-unix:/tmp/.X11-unix -v ~:/home/autowise/ -w /home/autowise/ -v /opt/ros/kinetic/share/aw\_models:/opt/ros/kinetic/share/aw\_models registry.autowise.ai/awcar /bin/bash

autowise@autowise:/opt/ros/kinetic/share/aw\_launch/config/conf$ docker cp tasks/ ace750bfcd6d:/opt/ros/kinetic/share/aw\_launch/config/conf

xterm -e "source ~/.autowise/setup.sh;roslaunch aw\_hdmap hdmap\_runtime\_env.launch" &

xterm -e bash -c 'roscore' &

## 服务器相关：

scp -r tasks/ 192.168.2.231:/opt/ros/kinetic/share/aw\_launch/config/conf

ssh -X [autowise@192.168.2.231](mailto:autowise@192.168.2.231)

mv tasks/ tasks\_old

scp blacklist 192.168.2.231:/home/autowise/qyc

生成JSON位置：/opt/ros/kinetic/share/aw\_global\_planning/data

## Jira test case

autowise@autowise:~/autowise\_test/log\_based\_simu$ ./savecase.py -s 60 -e 90 /data/suzhou\_station\_square/20200611/2020\_06\_11\_09\_37\_00\_arts16\_1\_suzhou\_station\_square\_0.bag ./cases/test\_SUZHOUXC-236/

git checkout suzhouxc197

git reset --hard

git clean -df

rosrun aw\_bag search record\_time=2020-05-28%

rosrun aw\_bag search path=/data/shanghai\_songjiang% record\_time=2019-11-14%

./savecase.py -s 60 -e 90 /data/suzhou\_station\_square/20200611/2020\_06\_11\_09\_37\_00\_arts16\_1\_suzhou\_station\_square\_0 ./cases/test\_SUZHOUXC-236

mysql -h 192.168.2.224 -u root -p regression\_test

desc evaluationrecord

docker ps | grep awcar

docker cp 20f0f9be9bfc:/opt/ros/kinetic/share/aw\_global\_planning/data /home/autowise/qyc/

scp -r 192.168.2.231:/home/autowise/qyc/data/ ./

python new\_playcase.py cases/test\_SUZHOUXC-197/ --exit --run\_id=10000