

Unable to maneuver vehicle through sharp curve based on Humble #3369

✓ Answered by takayuki5168

JianKangEgon asked this question in Q&A

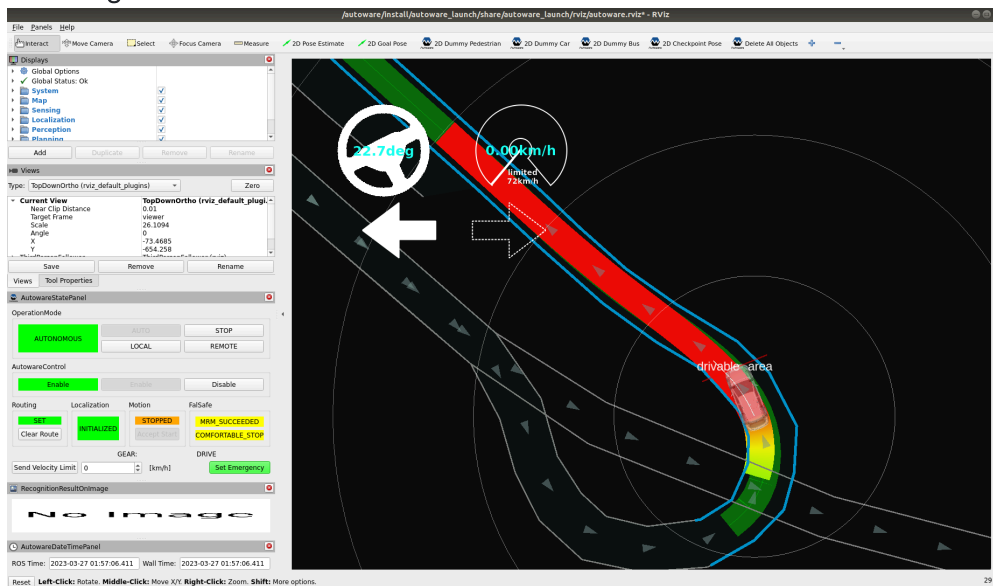


JianKangEgon on Mar 27, 2023

Collaborator

We are now testing the Autoware humble version (docker image: humble-latest-prebuilt), using planning simulator for verification of control module. The vector map is available at [here](#)

However, the current controller can not follow the trajectory exactly as the following:



In the previous version (Autoware galactic), I used the same map and performance would be much better (vehicle could pass through the curve successfully every time basically). I've compared the difference between these two versions. The kernel algorithms and parameters are basically the same. Only the control frequency is set as the half, even if I modify the control period, there is not any improvement.

I would keep configuring the parameter to make it and very much appreciate it if any suggestion.

Category



Q&A

Labels

None yet

2 participants



↑ 1



Answered by **takayuki5168** on Apr 7, 2023

Does this have something to do with trajectory planning?

Yes, it's related to obstacle_avoidance_planner.

Have you ever changed some params in planning module?

[View full answer](#) ↓

**takayuki5168** on Mar 27, 2023

Collaborator

I will look into it.



1



1

9 replies

[Show 5 previous replies](#)**takayuki5168** on Apr 3, 2023

Collaborator

Please make this discussion answered if the problem was resolved.

**JianKangEgon** on Apr 4, 2023

Collaborator

Author

OK, this topic is still ongoing, will perform road test afterwards. I'll close this discussion when everything done.

**JianKangEgon** on Apr 7, 2023

Collaborator

Author

edited ▼

[@takayuki5168](#), hi, I've tried the docker tag "[humble-latest-prebuilt-amd64](#)", but is still not good as expected. Does this have something to do with trajectory planning? Have you ever changed some params in planning module? much appreciate it if any idea.

**takayuki5168** on Apr 7, 2023

Collaborator

Does this have something to do with trajectory planning?

Yes, it's related to `obstacle_avoidance_planner`.

Have you ever changed some params in planning module?

Since I reported that it worked well, I didn't change. I don't have any idea for now.



Marked as answer

Answer selected by **JianKangEgon**