

Autoware Sensing Perception Working Group Meeting 2024/10/30 #5387

drwnz started this conversation in **Working group meetings**



drwnz 3 weeks ago

Collaborator

edited ▾

Administrative

- [Previous meeting](#)
- **Meeting time:** Every second Wednesday, 10am UTC (alternating with Mapping WG)
- [WG Google Drive](#)
- [Wiki page for this Working Group](#)
- [Shared issue list](#)

Attendees

▼ Chaired by David

- Ryohsuke
- Fatih
- Kok
- Max
- Amadeusz
- Vivid
- David W
- Taekjin

Agenda

- Introduction of new attendees
- Review of [Issue List](#) and assignment
- Review of [Project Board](#) and assignment

Discussion topics

- Development of Autoware Core
 - Perception part: will not port ML models
 - Need a release plan and decide release cadence
 - Package quality for Autoware core: <https://ros.org/repos/rep-2004.html>
 - Max: meant for minimum viable product, but also has the highest code quality, but the bus projects etc will still run on Universe. Don't we still require the high code quality in parts of Universe?

Category



Working group meetings

Labels

meeting:sensing-p...

2 participants



- Fatih: Aim is to improve quality in core first.
- Amadeusz: refactoring Autoware with ROS buildfarm in mind, is there any plan to move packages to buildfarm?
 - Yes, prioritizing with core
- Autoware Launcher:
 - <https://github.com/orgs/autowarefoundation/discussions/5313> from Fatih
 - One suggestion about automating the launcher from Taekjin
 - Handwriting the launch is not scalable and sustainable
 - Fatih: can also use python GUI tools to realize this
 - Example of organization of internal connections:
 - https://github.com/autowarefoundation/autoware.universe/blob/main/launch/tier4_perception_launch/launch/object_recognition/detection/detection.launch.xml
 - Fatih: we might not need to do the shift gradually, but could move all the core packages and write the autogeneration tool for the core packages. Existing launch files will still refer to packages from both core and universe, but it can be tested for the core packages.
 - In summary: have some configuration file for each package
 - Note to self: have a look at Dear ROSNodeviewer
 - Amadeusz: Simplifying the launchfile hierarchy improves performance, is that the motivation?
 - The main reason is to make it easier to configure Autoware
 - Not sure if ROS backporting will take time if ros2 launch modifications are made
- Yolo V10: 🦜 [feat: add yolov10 node](#) autoware.universe#9198
- CUDA upgrade:
 - <https://github.com/orgs/autowarefoundation/discussions/5300>
 - Actively being worked on by Amadeusz
 - ROS2 Jazzy will be necessary to upgrade to CUDA anyway, and supporting new TensorRT version will be backwards compatible anyway

Action items

- []

↑ 1

1 comment

Oldest

Newest


Top



xmfcx 3 weeks ago Maintainer

edited ▼

- [Improve the Autoware Launch System #5313](#)
- [Implementing Autoware Core #5365](#)
 - Release plan to be made concrete in documentation
 - <https://ros.org/reps/rep-2004.html>
 - Let's iteratively improve the quality

-  [feat: add yolov10 node](#) autoware.universe#9198
- [Proposal for CUDA upgrade #5300](#)

↑ 1

0 replies