

obstacle_segmentation pointcloud frequency low #3003

✓ Answered by miursh MrOCW asked this question in Q&A



MrOCW on Nov 4, 2022

Hi, am using an OS1-32 lidar on 1024x20 mode. The raw pc data is at about 15Hz but /perception/obstacle_segmentation/pointcloud is at 4 to 5 Hz. This seems to cause issues like missed or late detections for lidar_centerpoint. Not sure if this is a bug or if i should reduce to 512x10 mode?

I am running on a Jetson Orin AGX with sudo jetson_clocks activated.

↑ 1

Category



Q&A

Labels

None yet

6 participants



Answered by miursh on Nov 14, 2022

@MrOCW I'm sorry for my late response.

If it is because of shortage of CPU power, setting lower resolution (like 512x10) might help.

I haven't run this algorithm on Jetson Orin AGX, so I can't tell about the performance issue on it.

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takayuki5168 on Nov 9, 2022

Collaborator

@yukke42

↑ 2

2 replies



yukke42 on Nov 10, 2022

@miursh @badai-nguyen May I ask you to answer the question?



shmpwk on Nov 10, 2022

Maintainer

@MrOCW Could you share your rosbag?



miursh on Nov 14, 2022

Collaborator

@MrOCW I'm sorry for my late response.

If it is because of shortage of CPU power, setting lower resolution (like 512x10) might help.

I haven't run this algorithm on Jetson Orin AGX, so I can't tell about the performance issue on it.

Could you check the cpu and memory usage?

Also if you could share the rosbag, that would help us to investigate this problem.



Marked as answer



1



1

2 replies



MrOCW on Nov 14, 2022

Author

i've changed it to 512x10 and that indeed helped. thank you!



1



1



hzkkk1997 on Sep 15, 2023

Hello~ May I explain what mode this 1024x20 is? Can it be understood as the resolution of LiDAR?

Answer selected by **MrOCW**