

CARET, a performance analysis tool for Autoware #2630

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Hi community members!

I'd like to introduce [CARET](#), a performance analysis tool for Autoware and other ROS 2 Apps.

We are developing CARET to observe both timing and latency of callback execution and topic communication. CARET can show you how a certain topic message is propagated to nodes with combining those CARET can observe. For example, graph called message flow shows it as below. You will find how to understand this graph on [this page](#).

Category

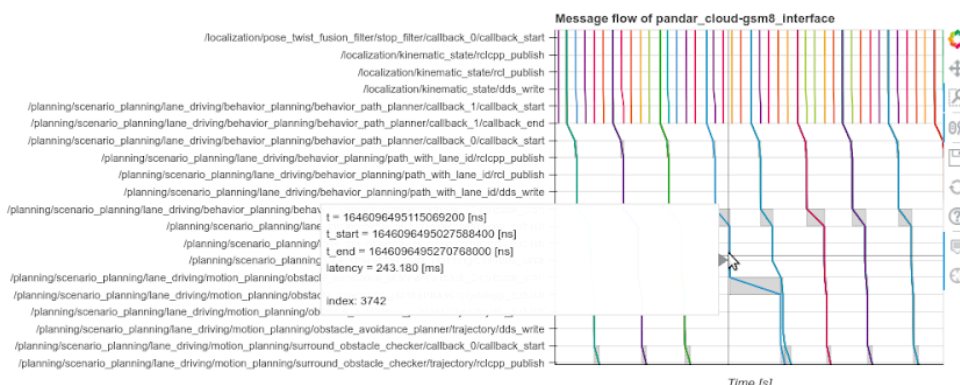


Show and tell

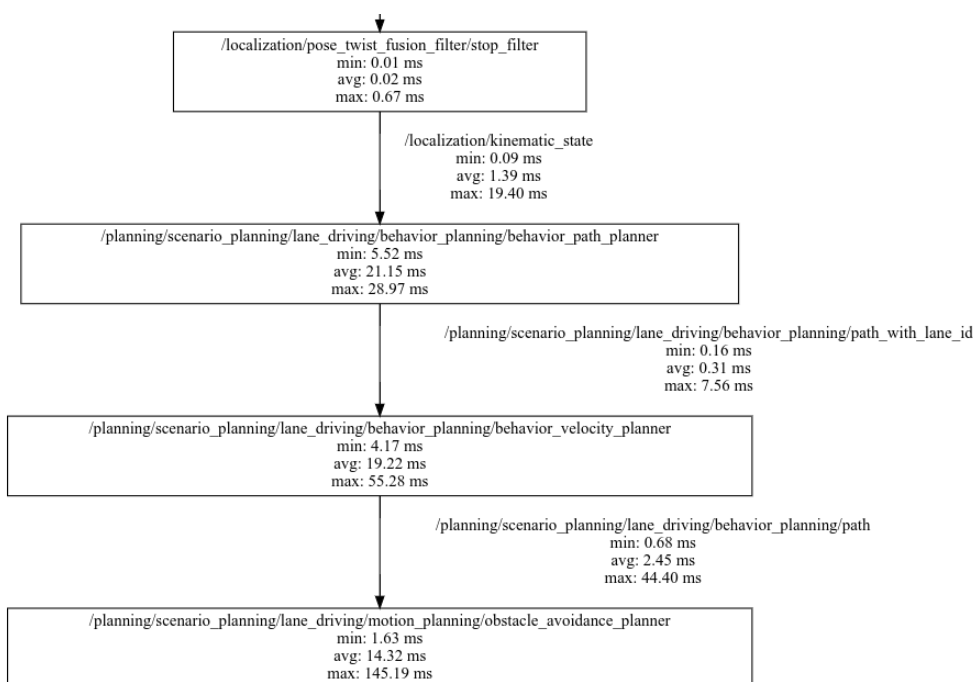
Labels

None yet

1 participant



You can check average of latency elapsed in each callback and communication briefly with another style of figure.



CARET has concept similar to [ros2_tracing](#) which gives some ideas to us. You don't have to change any source code for tracing Autoware basically as well as ros2_tracing. However, there is some exclusion. For tracing a complicated node, like `/sensing/lidar/concatenate_data` node which stores multiple topic message in its buffer, you may need add some codes in the future. My colleague will introduce this feature when it is unveiled as OSS.

Please read [CARET's documentation](#) for more details if you are interested in and try it. When you confront with any issue on using CARET, please let us know it via [Issues](#).

Best,



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0 comments