Feature/open planner #894   [New issue]

🔀 Merged   **hatem-darweesh** merged 6 commits into `develop` from `feature/OpenPlanner`   ⧉ on Dec 4, 2017

💬 Conversation 6   ⊶ Commits 6   ☑ Checks 0   📄 Files changed

hatem-darweesh commented on Nov 14, 2017

Status

**PRODUCTION **

Description

Split OpenPlanner Into multiple nodules
Stage 1:

1. Update OpenPlanner library latest development from feature/OpenPlanner-dev
2. Test and fix backward compatibility for current OpenPlanner nodes (way_planner, dp_planner)
3. Add new package to planning/motion/ : op_local_planner
4. Add new node for candidate trajectory generation: op_trajectory_generator
5. Add UI launcher in the Runtime Manager
6. Tested using way_planner and waypoint loader for global path generation
7. Tested with simulation and rosbag data.

Todos

☐ Common parameter
  separate common local planning parameters from each node specific parameters
☐ Documentation

Steps to Test

1. Run op_trajectory_generator from runtime_manager/computing/motion

Reviewers

👤 aohsato   ●

Assignees

No one assigned

Labels

type:new-feature   version:autoware-ai

Projects

None yet

Milestone

No milestone

Development

Successfully merging this pull request may close these issues.

5 participants

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planning/OpenPlanner - Local
planning/op_trajectory_generator

2. Global path data should be available either by way_planner or waypoints_loader

3. current _pose should be available either by live localization from rosbag or simulation.

4. Results could be observed on rviz, green roll outs coming out from the center of the car parallel to the global path.

👍 1

yk-fujii and others added 3 commits 7 years ago

Update   9c6cfcf
installation_with_drivepx2.md

— Update OpenPlanner libraries   f42a35e
(plannerh, simuh, utilityh) with the
l… …

— Add user interface option in   0794099
runtime manage for local_planner and
o… …

hatem-darweesh requested a review from aohsato
7 years ago

hatem-darweesh added the type:new-feature label
on Nov 14, 2017

hatem-darweesh assigned aohsato on Nov 14, 2017

— Add new Node for object polygon   efe17ab
representation and tracking (kf_con…
…

dejanpan commented on Nov 25, 2017

@hatem-darweesh this is a really large PR. Can you please explain where does the motivation come from? What are the exact benefits of this PR?

— Test Tracking …   eb5fe7c

hatem-darweesh commented on Nov 25, 2017   Author

@dejanpan It is part of TierIV requirements , to merge latest OpenPlanner into master branch by splitting it into separate nodes.
Objectives are:

- Separate different parts of OpenPlanner into small nodes
- Refactor and use latest development for the past 8 month.

👍 1

dejanpan commented on Nov 25, 2017

@hatem-darweesh so the code is now more modular. Is it also more performant?

hatem-darweesh commented on Nov 26, 2017   Author

@dejanpan Yeah, current code is optimized, more readable and planning performance is much faster. (100 hz on average)

yk-fujii changed the base branch from `master` to `develop` 7 years ago

yk-fujii commented on Nov 27, 2017

@hatem-darweesh
I changed the base branch to develop.
however, conflicts are occurring. Please resolve it.

`Merge branch 'develop' into` `86edef2`
`feature/OpenPlanner` ...

hatem-darweesh merged commit **86edef2** into `develop` on Dec 4, 2017

dejanpan commented on Dec 11, 2017

@hatem-darweesh @yk-fujii same here. It is impossible that change in 75 files is without bugs. Such PR must be thoroughly reviewed, discussed and there must be test.

gbiggs unassigned **aohsato** on Mar 24, 2019

mitsudome-r added the `version:autoware-ai` label
on Jun 14, 2022

mitsudome-r added the `version:autoware-ai` label
on Jun 14, 2022