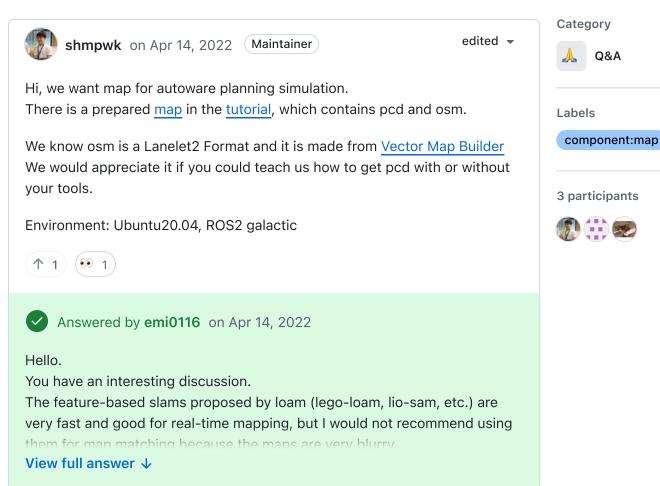


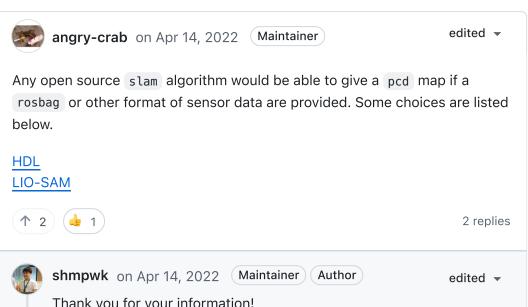
## Create map for autoware #2520







Oldest Newest Top



Thank you for your information!

We also consider to use interactive slam, which includes HDL, However interactive slam supports neither ROS2 nor ROS1 noetic, and only supports melodic or its less version.

So we decide to use LIO-SAM which supports ROS2.



shmpwk on Apr 19, 2022 (Maintainer) (Author)

As @emi0116 says, LIO-SAM is a little complicated.

It is better for us to use the easiest slam this time.

So finally, we use lidarslam\_ros2.



## emi0116 on Apr 14, 2022

Hello.

You have an interesting discussion.

The feature-based slams proposed by loam (lego-loam, lio-sam, etc.) are very fast and good for real-time mapping, but I would not recommend using them for map matching because the maps are very blurry.

If you can use ROS1, I suggest you use hdl\_graph\_slam or interactive\_slam. For ROS2, I have used

lidarslam\_ros2(https://github.com/rsasaki0109/lidarslam\_ros2), which is also good

(There was talk that it would also be used in navigation2, but it appears that work has now stopped.

ros-navigation/navigation2#1757



Marked as answer





3 replies



shmpwk on Apr 14, 2022 (Maintainer) (Author)

Thanks for the extremely useful information! We use ROS2 and prefer accuracy to speed and real-time performance since we are working on a prototype project. So lidarslam\_ros2 seems nice for us except stopping their work.



emi0116 on Apr 17, 2022

edited -

My comment was confusing.

It appears that the development of lidarslam\_ros2 is continuing, just that the move to make it the standard SLAM for ROS2 has stopped. (At least the maintainer seems to be actively commenting on issues.)





shmpwk on Apr 20, 2022 (Maintainer) (Author)

edited -

We finished making map by only using lidar. Thank you!



Answer selected by shmpwk