

Autonomy Software WG Meeting 2022/05/10 #2565

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



BonoloAWF on Apr 26, 2022

edited ▾

Administrative

- [Previous Meeting Minutes](#)

Attendees

► Chaired by Ryohsuke

Common Resources

- Bus ODD [software architecture proposal](#)
- Bus ODD [architecture design discussions](#)
- Bus ODD [candidate simulator comparisons](#)
- Bus ODD [milestone development plan](#)
- Autoware [contributors list](#)

Announcements

The meeting last week was cancelled due to national holidays in Japan and Turkey.

Autoware.Auto

- ☐ Updates on [bug fixes](#) and [documentation bugs](#)
- ☐ Release of Autoware.Auto v2.0.0

Autoware.Universe

- ☒ Bus [ODD issues](#)
- ☒ Autoware.Universe reported [bugs](#)
- ☒ Autoware [design discussions](#) and [demos](#)

Discussion topics

No topics this week.

Category



Working group meetings

Labels

meeting:software-wg

1 participant



Action Items

- ✓ [@armaganarsln](#) to create a Discussion for investigating radar in Autoware when he receives a new radar from SmartMicro -> He will do it once he receives the device.
- [@xmfcx](#) to create an issue to test the existing lidar-only perception pipeline with the data provided ✓ [Collect raw sensor data to test sensor drivers](#) autoware.universe#562 (comment)

Review of Issues and Discussions

The following Issues and Discussions were reviewed (see comments for details):

- ✓ [Potential collision risk with long obstacles](#) autoware.universe#833 - in progress
- ✓ [The output of the gnss_poser package is not suitable for ekf](#) autoware.universe#800 - we can either create a new msg or use 2 separate msgs. The msgs for localisation will be discussed in the Architecture WG meetings
- ✓ [Choose GPU device before running tensorrt_yolo 2D detection node](#) autoware.universe#736 - there is an existing API to select a device but tests are required on a machine with multiple GPUs
- ✓ [Add another crop_box_filter node](#) autoware.universe#703 - in progress
- ✓ [Collect rosbag of sensor data for camera](#) autoware.universe#680 - this will be split into smaller issues by Fatih
- ✓ [Implement any missing calibration tools](#) autoware.universe#679 - the opensource calibration tool needs to be tested on a rosbag
- ✓ [Ground segmentation fails for points behind the low objects](#) autoware.universe#669 - the rosbag will be split into smaller size since the bug occurs somewhere near the start so it is tricky to reliably reproduce
- 🔗 [feat\(control_performance_analysis\): add new functionalities to evaluate the control modules](#) autoware.universe#659 - Ali will review this again
- ✓ [Add TVM inference capability](#) autoware.universe#628 - NN packages should be separate to handle the download step and allow a user to provide custom NN if required. Core will provide inference via TVM but Universe still implements tensorRT. See 🔗 [Correct waypoint_follower dependnecy about message header](#) #226
- ✓ [Create speed_bump behavior module](#) autoware.universe#611 - in progress
- ✓ [Review of the processing of turn_signal_decider](#) autoware.universe#605 - solution appears to have been merged
- ✓ [Implement sensor drivers for ROS 2](#) autoware.universe#551 - ITRI can confirm which sensors still require ROS 2 drivers
- ✓ [Wrong path planned by avoidance module in a special case](#) autoware.universe#706 - in progress

- [🔗 the "crop_box_filter" can cause error in the subsequent module.](#) [autoware.universe#705](#) - in progress
- [🔗 Problems when add NPC to the scenario editor](#) [autoware.universe#558](#) - closed
- [🔗 Fix errors of clang-tidy-differential](#) [autoware.universe#456](#) - low priority
- [🔗 unit test of trajectory follower sometimes fails randomly](#) [autoware.universe#432](#) - closed (related to [🔗 Feature/dataprocessor](#) #649)
- [🔗 Modified scan2image & calibration_test for calibration_publisher node](#) #101 - Robotec will provide artificial dataset of a large pointcloud to test
- [🔗 Runtime Manager, update for immediately reflection of sys CPU setup](#) #279 - TomTom has open sourced their tool for converting from HD Map (TomTom AutoStream) to Lanelet 2 format required by Autoware. The conversion is offline even though AutoStream supports live map updates. Autoware does not yet support online updates of maps.
- [🔗 Update manuals](#) #275 - Kenji created a tool to visualise the Autoware system, showing the relationship between launch files.
- [🔗 Add synchronization system for perception](#) #234 - TSC decision was to use the TierIV simulator as the default for the bus ODD. The simulation working group will continue to investigate Carla and MORAI Sim performance and suitability for use with Autoware.

↑ 1

0 comments