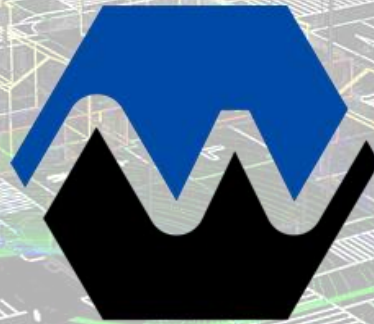


Autoware Updates 2018

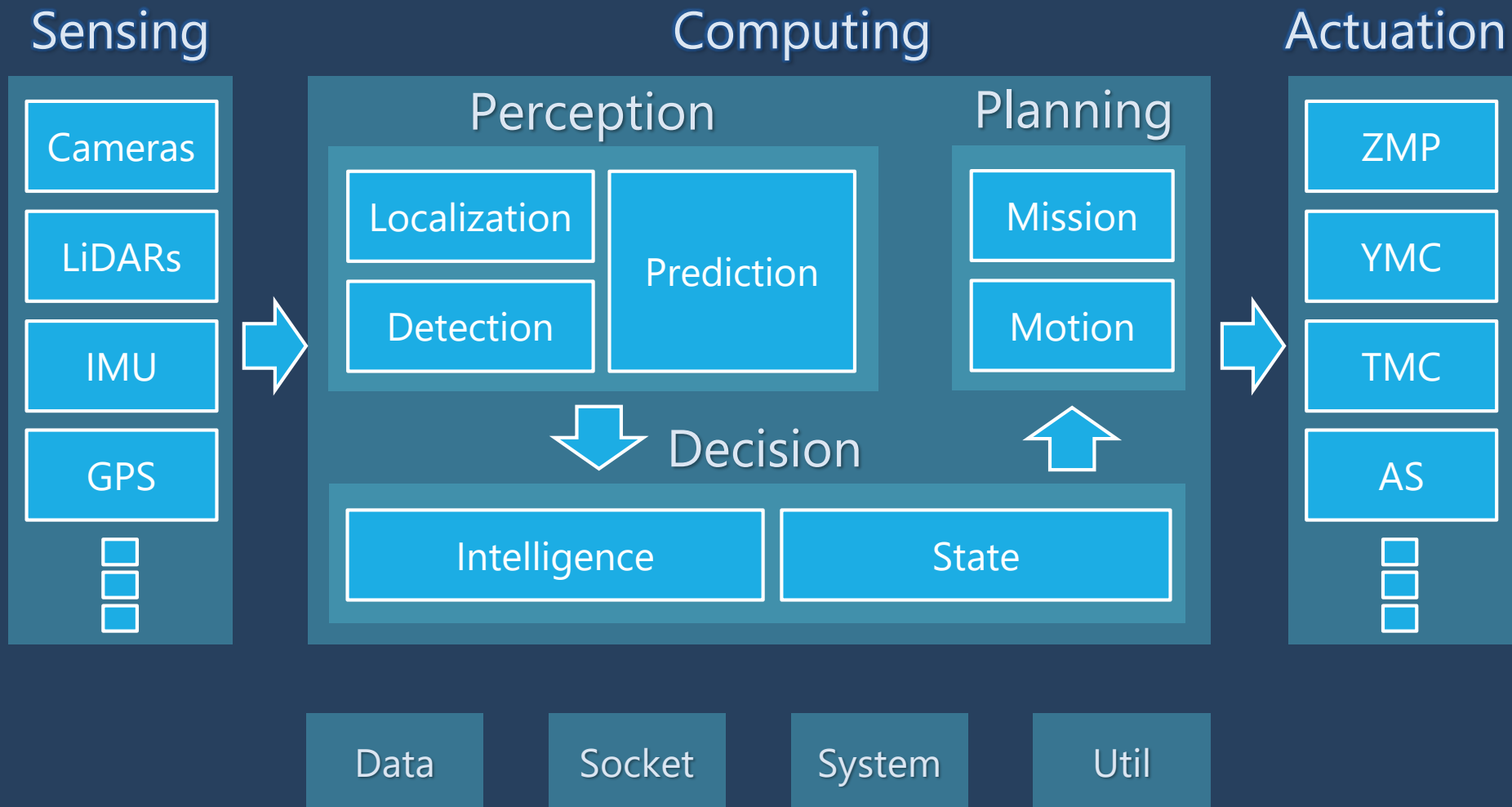
“Platform to Service”

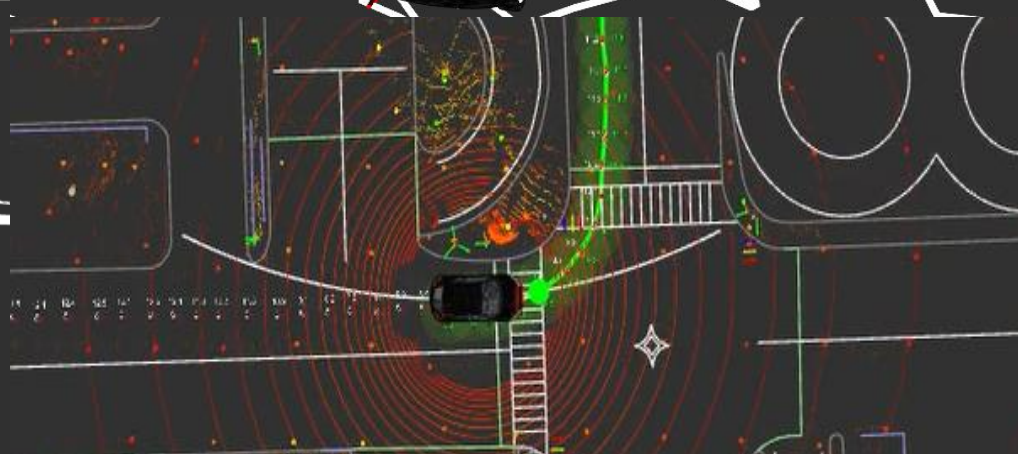
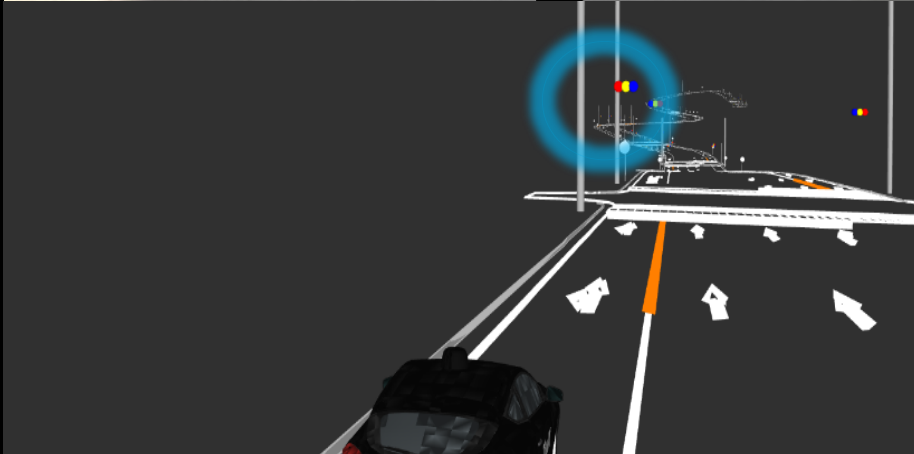
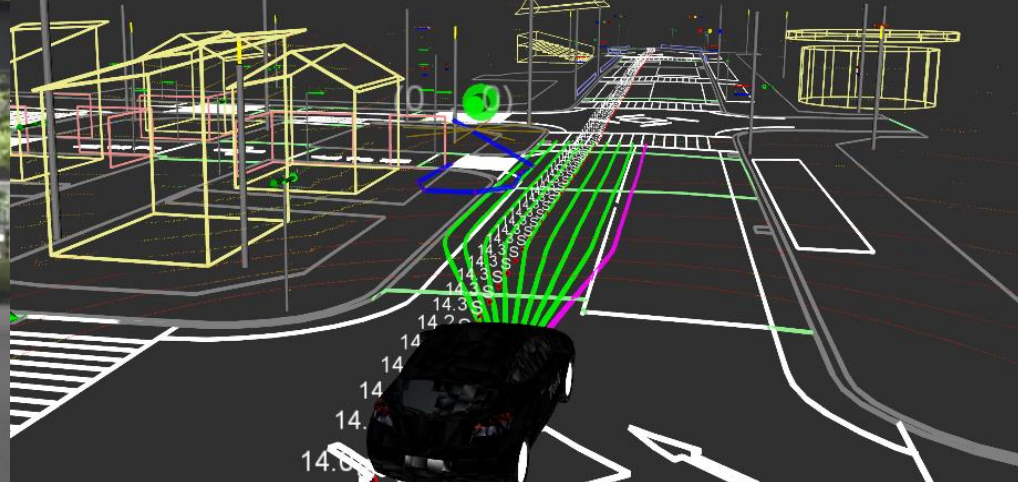
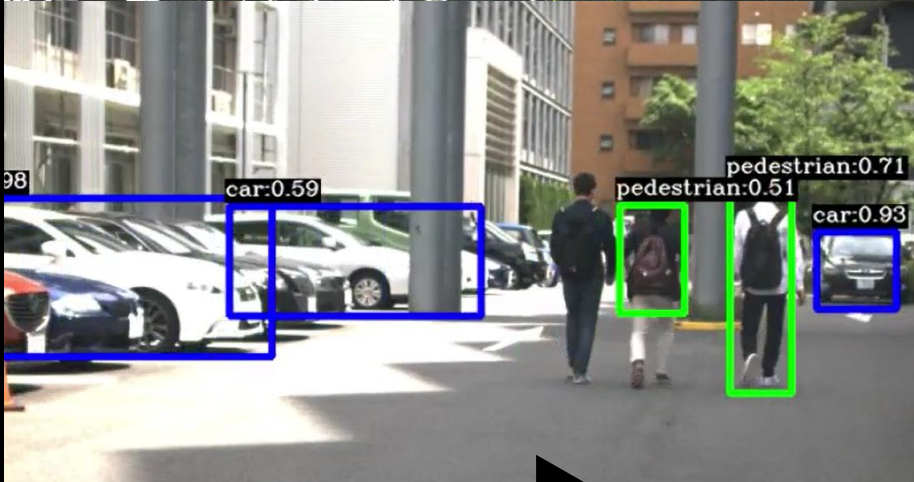
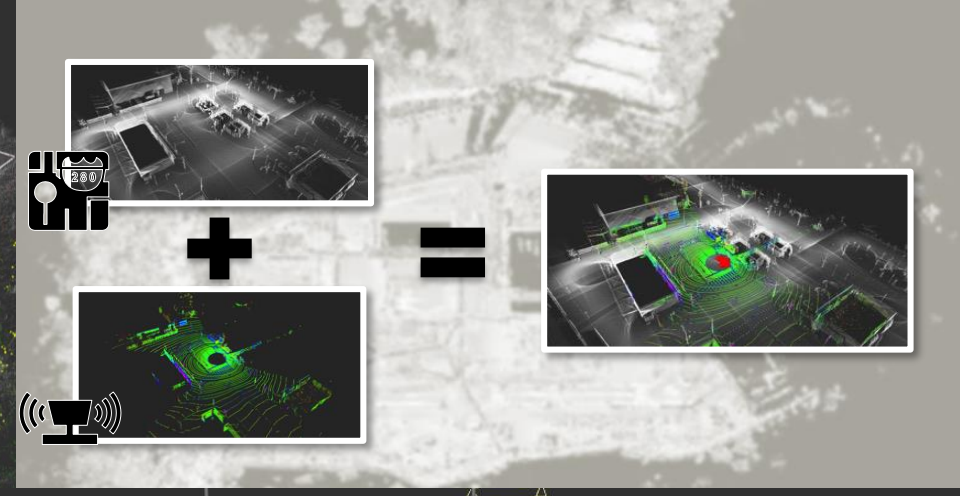


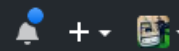
Akihito Ohsato
Lead Engineer
Tier IV, Inc.



AutoWare





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Branch: master

[New pull request](#)[Create new file](#)[Upload files](#)[Find file](#)[Clone or download](#)[kfunaoka](#) [Release] 1.8.0 (#1487)

Latest commit 88a1f08 13 days ago

[docker](#)

[Feature] Cross compile for NVIDIA DriveWorks (#1447)

25 days ago

[docs](#)

[Hotfix] Revise README.md (#1326)

3 months ago

[ros](#)

Delete multiple 1.7.0 commit messages in each CHANGELOG

14 days ago

[ui](#)

Merge pull request #1173 from CPFL/feature/remote_monitor

6 months ago

[vehicle](#)

Ignore when mode=-1

2 years ago

[.gitignore](#)

fix unnecessary change

3 months ago

[.gitmodules](#)

[fix] Pin platform_automation_msgs submodule (#1420)

a month ago

[.travis.yml](#)

[Fix] Clean up Build-Docker for each environments (#1433)

a month ago

[AUTHORS](#)

Add conference paepr information

5 months ago

[LICENSE](#)

Initial commit for public release

3 years ago

[README.md](#)

[Hotfix] Revert Slack URI in README.md

2 months ago

[THANKS](#)

Update THANKS

11 months ago

[README.md](#)

1.5.0

5ff7722

Autoware Ver.1.5.0

Edit

yk-fujii released this on 21 Sep 2017 · 812 commits to master since this release

Assets 2

Source code (zip)

Source code (tar.gz)

Release v.1.5.0 #763 / #809

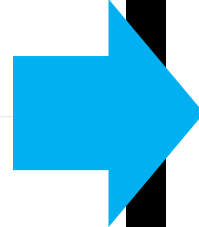
New Features

- Add Web-UI
- Add Decision Maker [WIP]
- Add GarminGPS support
- Add multiple cross-walk detector
- Add ENet image segmenter
- Add aarch64 support and NVIDIA DrivePX2 installation manual
- Add simulated obstacle creator for astar planning/dp_planner
- Fix docker files, Update nvidia-docker version.
- Fix some issues.

Demos/Documentation

Known Issues

ROSCon 2017 VANCOUVER



Latest release

1.8.0

88a1f08

Verified

Autoware Ver.1.8.0

Edit

kfunao released this 13 days ago

Assets 2

Source code (zip)

Source code (tar.gz)

New Features

- Results of vision detector and lidar detector can be combined by [range_vision_fusion](#) (#1419).
<https://www.youtube.com/watch?v=GEUVmO7xWDA>
- Colors of vision data can be projected into lidar data by [pixel_cloud_fusion](#) (#1297).
https://www.youtube.com/watch?v=KhcEpT_3GB4
- [Fake perception](#) generating fake object and pointcloud message (#1439).
<https://www.youtube.com/watch?v=F7yCnQz1FmQ>
- Cross build for NVIDIA DRIVE PX2 (#1447) and generic aarch64 (#1433).
The build time for NVIDIA DRIVE PX2 is shortened dramatically.
- [Docker for 96boards](#) (#1356).
- [Drivers of Sick LD-MRS lidar](#) (#1287).
- [Grid divider of Point Cloud Map](#) (#1271).
- Convenient [autoware_bag_tools](#) that rename frame IDs (#1307) and extract GN
- Using TF generator when tf.launch is not given (#1239).
- Pure pursuit publishes deviation of current position (#1357).
- Can limit maximum scan range of ndt_mapping (#1412).

Improvements

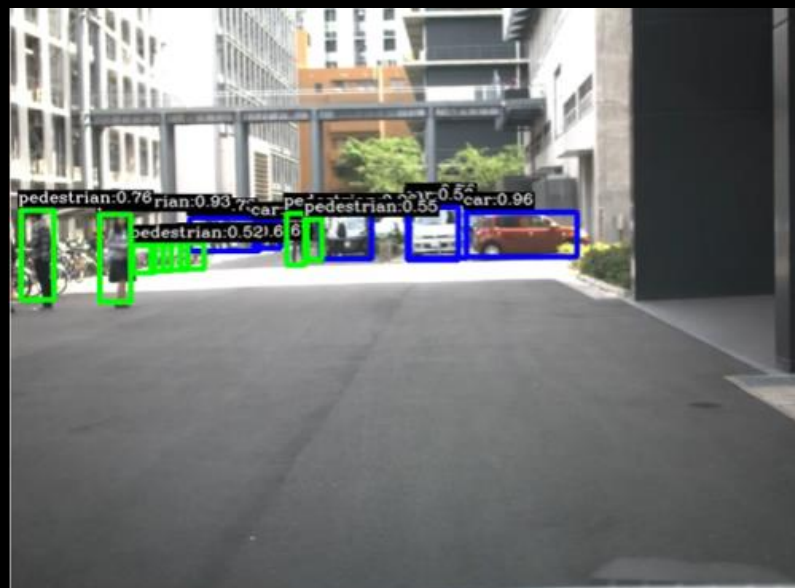
- Euclidean cluster classifies pointcloud more precisely (#1426)

ROSCon JP '18

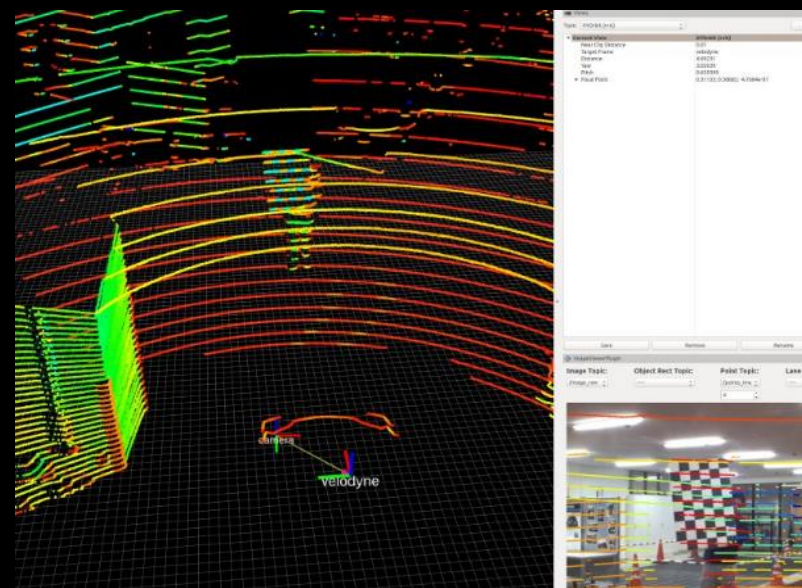
Sensor drivers



YOLO v3



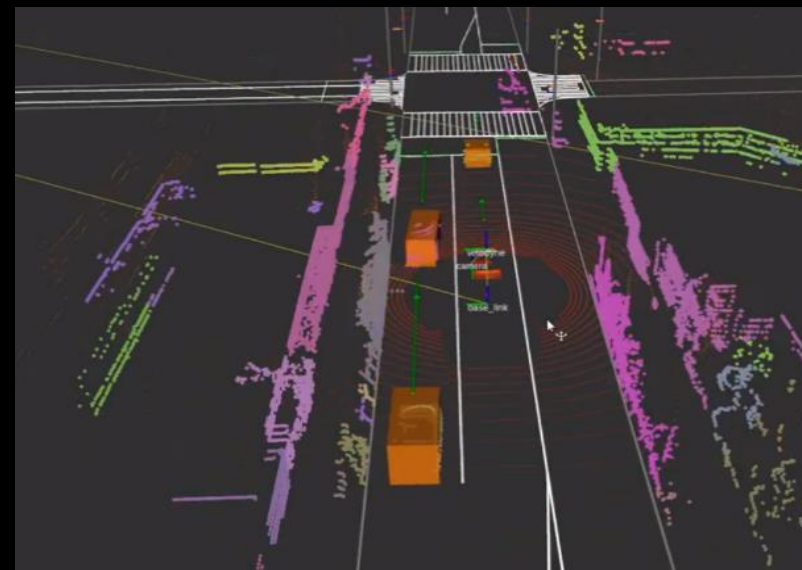
Calibration Tool



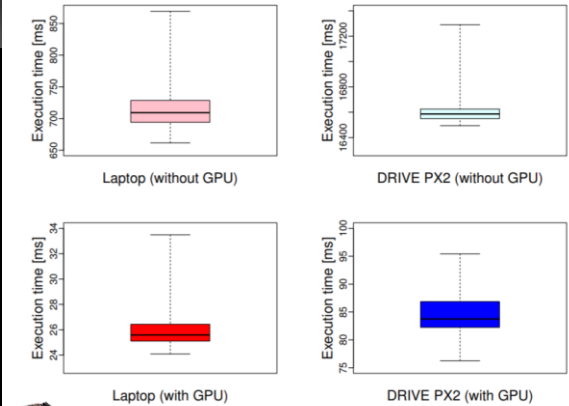
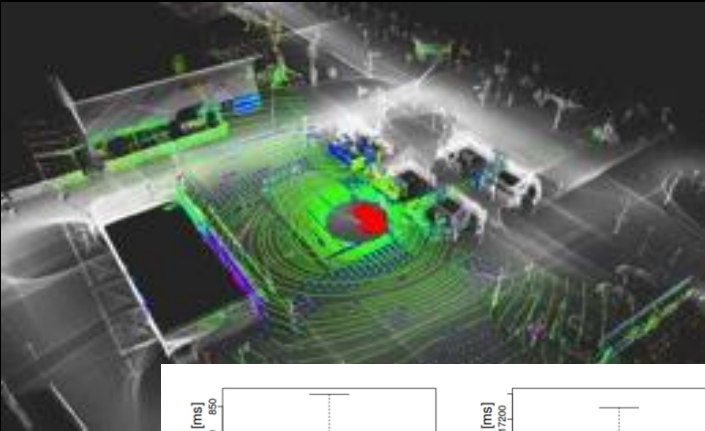
Pixel Cloud Fusion



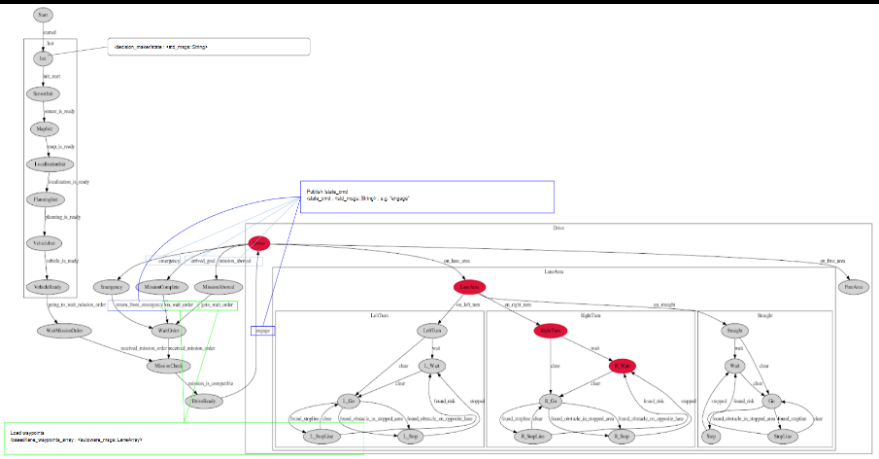
IMM-UKF-PDA Tracker



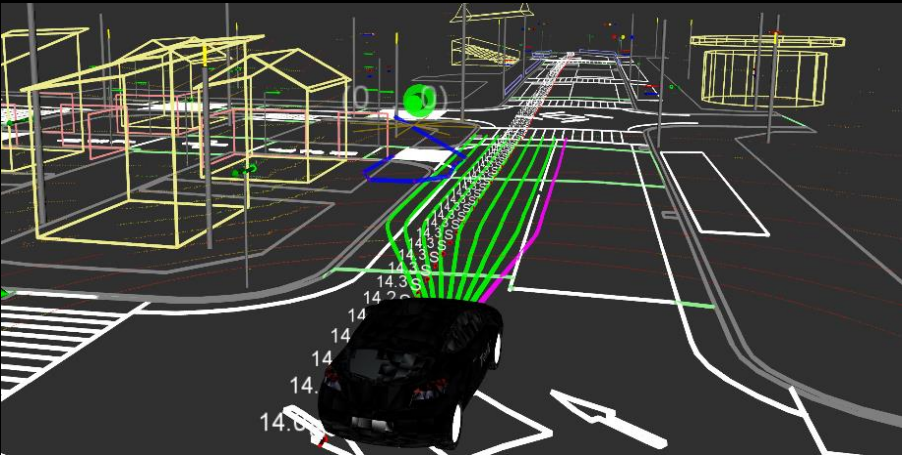
NDT Localization on GPU



Decision Making/State Machine



Lattice based Planner



Autonomoustuff Lexus



Yamaha Golfcar





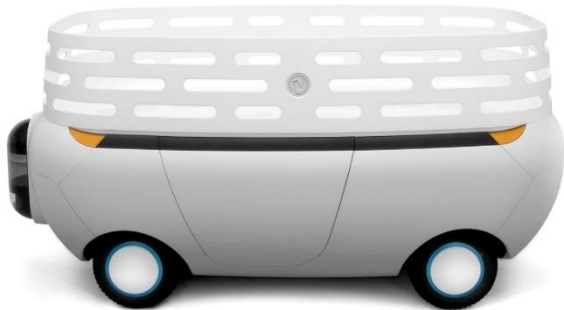
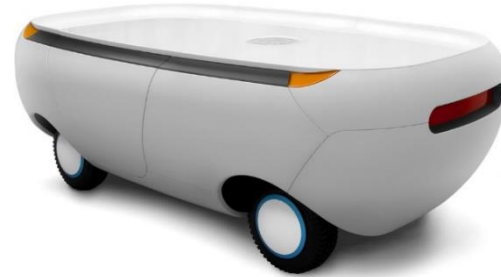
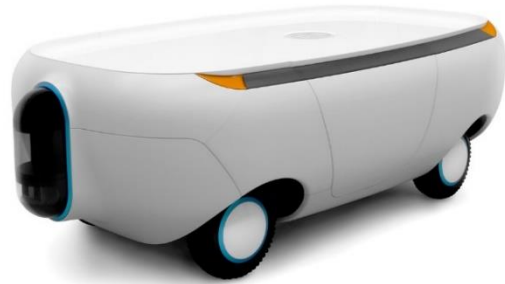
Apex.AI



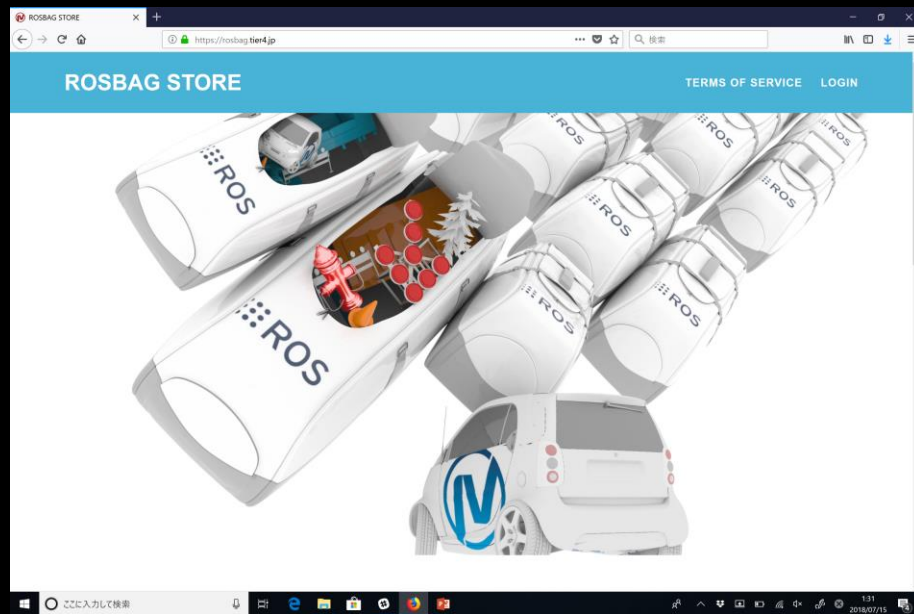
Intelligent Vehicle

11:30	Christopher Ho (Apex.AI, Inc), Sumanth Nirmal (Apex.AI, Inc), Dejan Pangercic (Apex.AI, Inc), Shinpei Kato (Tier IV, Inc), Jan Becker (Apex.AI, Inc)	<i>ROS 2 on Autonomous Driving Vehicles</i>	Over the past 10 years, ROS 1 has proven itself to be the framework of choice for prototyping and developing large robotic applications. Many limitations preventing ROS 1 from being used in production applications have been discovered over the years, and after significant prototyping, ROS 2 makes great headway in making ROS 2 suitable for production. Autonomous driving is the next great technology waiting to be realized and transform our society. A full autonomous driving stack is inarguably a large robotic system, and consequently ROS 2 is the right framework upon which to develop a full autonomous driving stack. To prove this, we have developed a part of the autonomous driving stack based on ROS 2.
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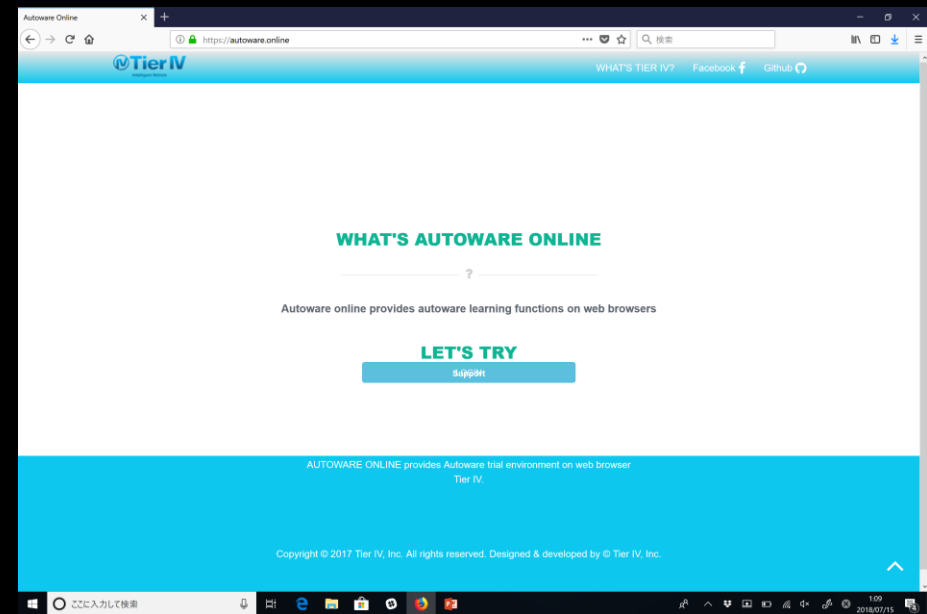




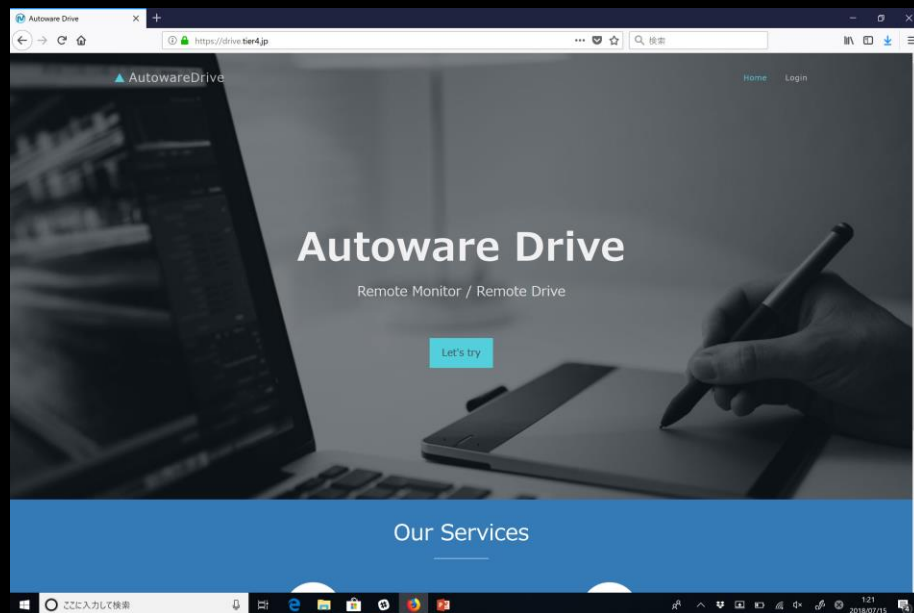




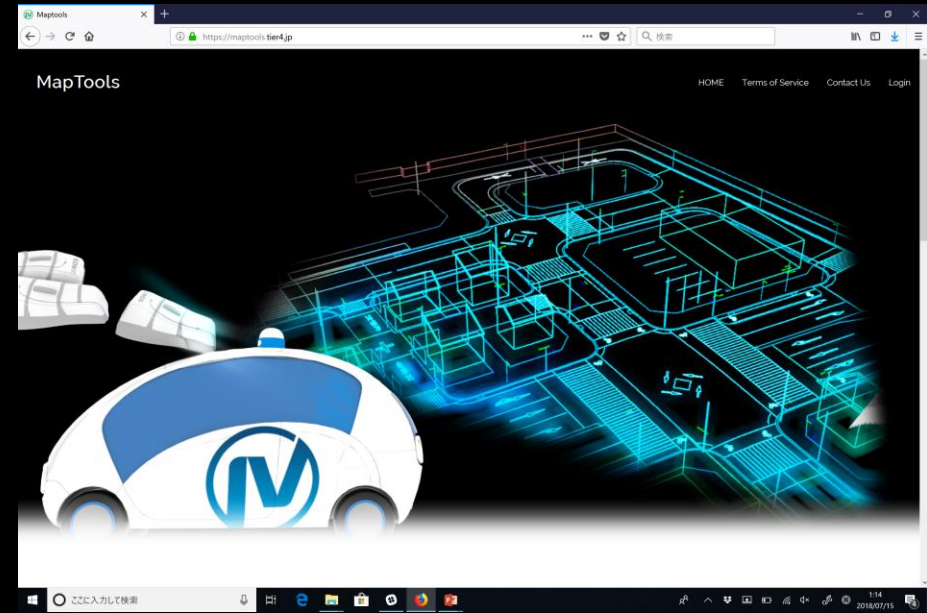
<https://rosbag.tier4.jp>



<https://autoware.online>



<https://drive.tier4.jp>



<https://maptools.tier4.jp>

Show

10

 entries

Search:

#	Place	Platform	File Name	Size(MB)	LIDAR	CAMERA	GNSS	IMU	Radar	Actions
1	Nagoya	ZMP	moriyama_2015-02-28_01.bag	8,332	-	-	-	-	-	
2	Nagoya	ZMP	moriyama_2015-03-24_01.bag	17,921	-	-	-	-	-	
3	Nagoya	ZMP	moriyama_2015-03-24_01.bag	17,921	-	-	-	-	-	
4	Nagoya	ZMP	NagoyaStation_part5_20151223.bag	32,257	-	-	-	-	-	
5	Nagoya	ZMP	moriyama_2015-06-11_01.bag	26,859	-	-	-	-	-	
6	Nagoya	ZMP	moriyama_2015-06-11_02.bag	8,885	-	-	-	-	-	
7	Nagoya	ZMP	NagoyaStation_part6_20151223.bag	59,159	-	-	-	-	-	
8	Nagoya	ZMP	nagoya_2017-04-27_01.bag	33,734	-	-	-	-	-	
9	Nagoya	ZMP	nagoya_2017-04-27_02.bag	37,617	-	-	-	-	-	
10	Nagoya	ZMP	nagoya_hdl64s2_20170427122245.rosbag.bag	37,617	-	-	-	-	-	
#	Place	Platform	File Name	Size(MB)	LIDAR	CAMERA	GNSS	IMU	Radar	Actions
Showing 1 to 10 of 202 entries							Previous 1 2345...21Next			

LOCATION

JAPAN

Tier IV



ABOUT ROSBAG STORE

ROSBAG STORE is an online storage room of ROSBAG files created by [Tier IV](#).

Automan

Alpha Version

Automan is an open self-driving AI.

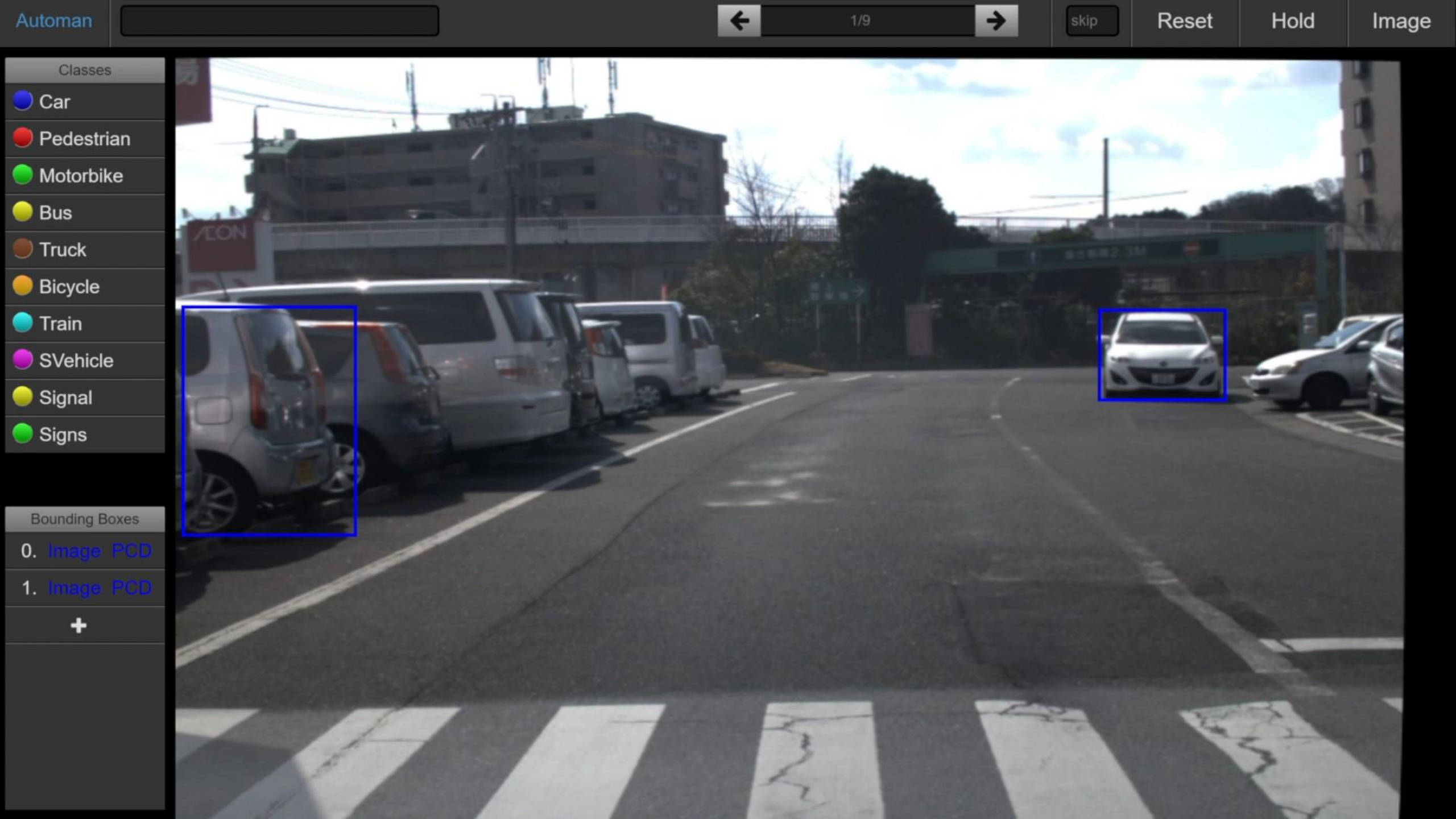
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Automan Services





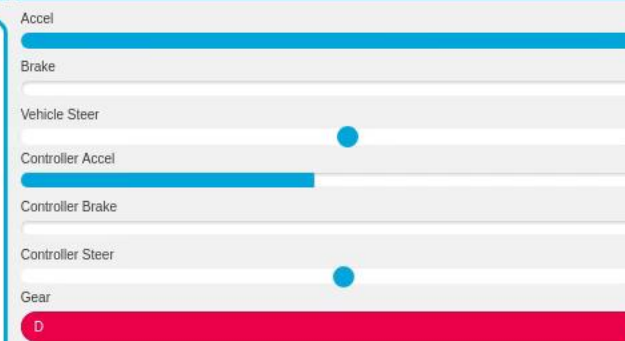
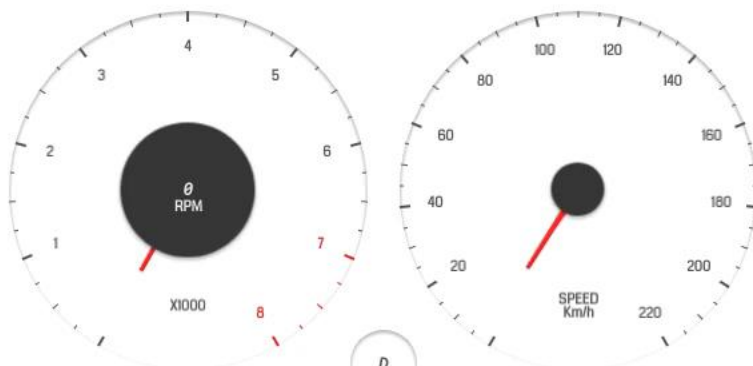
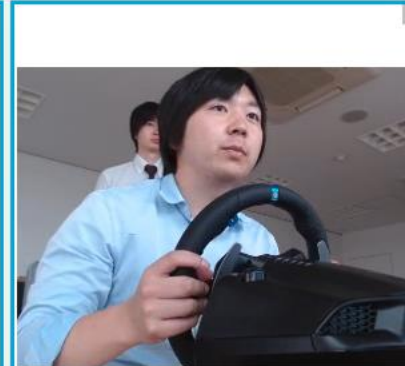
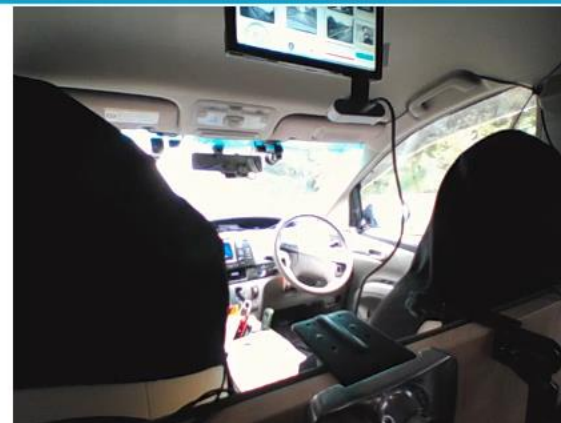
Vehicle Info

Speed: 2.23 km/h

Current Target Speed: 6.460000 km/h

Next Target Speed: 14.854683 km/h

State: MoveFwdStraight



EMERGENCY OFF

Remote



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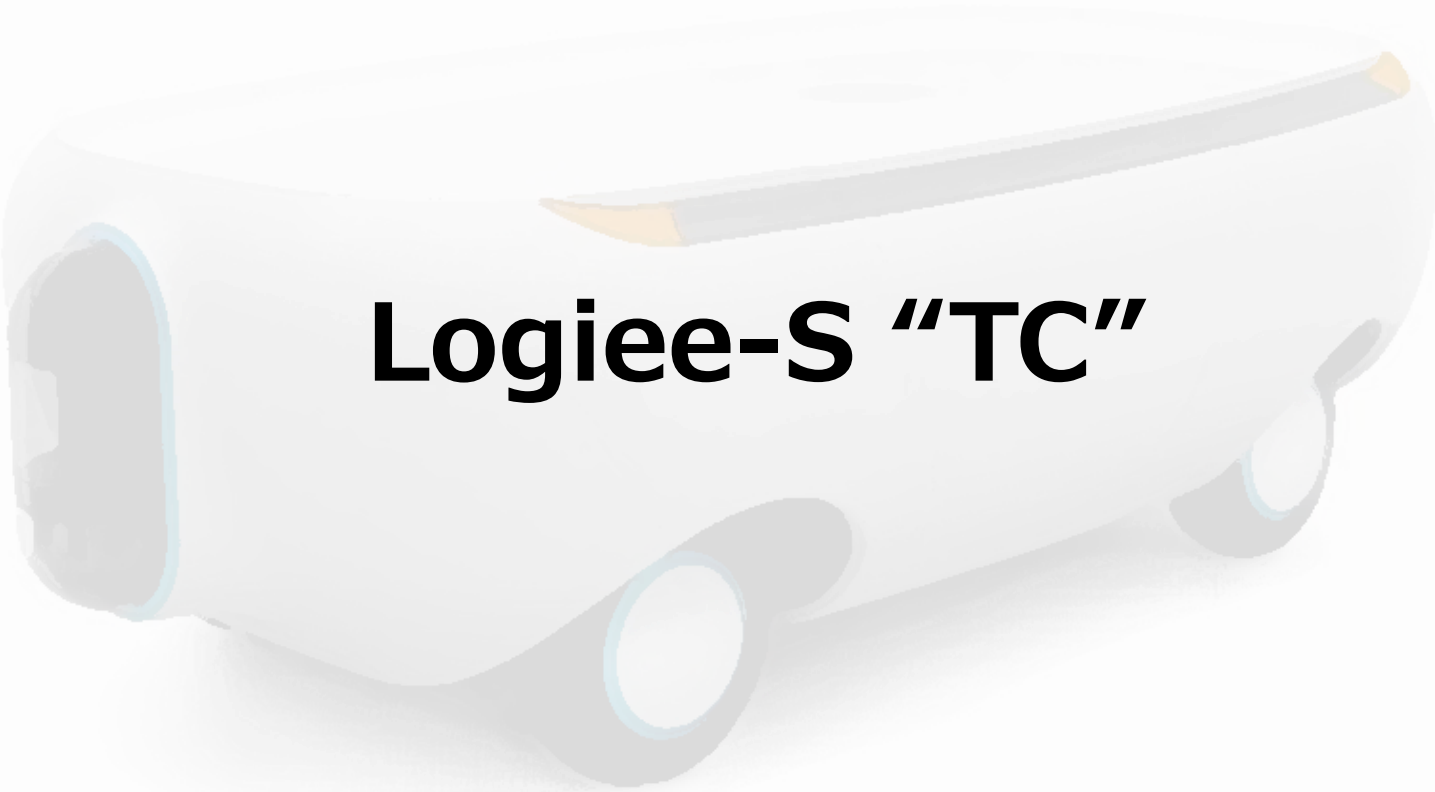
Open-Source To Self-Driving

Get Docker

ROSCON JP





A white, rounded rectangular object, possibly a smart display or a small robot, with a pencil resting on its top surface. The object has a camera lens on the front left and two circular sensors or lights on the bottom. The text "Logiee-S 'TC'" is overlaid on the front of the object.

Logiee-S "TC"



Intelligent Vehicle