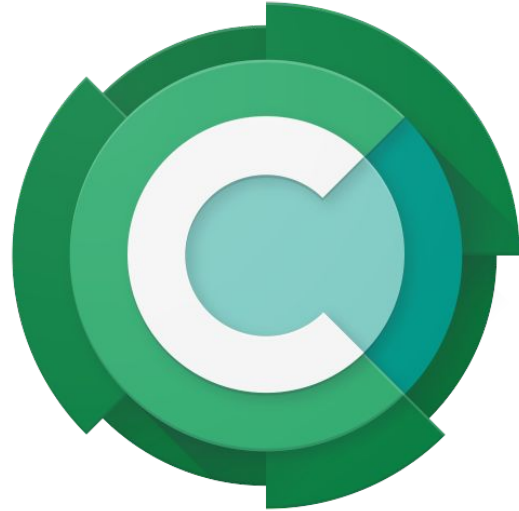# Cartographer Open House

June 6, 2017

What landed on master? • `cartographer`

- First unstable release ([#295](#)).
- Evolution:
  - Improvements to 3D loop closure detection ([#296](#)).
  - Simplified configuration of uncertainty ([#307](#), [#308](#), [#309](#))
- Lifelong:
  - Refactor multi-trajectory support to keep data separate for each trajectory ([#256](#)) in preparation of deletion of data from the optimization problem.
  - Beginnings of pure localization ([#283](#)).

What landed on master? • `cartographer_ros`

- Evolution:
  - Use intensities of [PointCloud2](#) in the asset_writer ([#348](#)).
  - Added an assets pipeline demo for 3D ([#352](#)).
  - Better tuning for Revo LDS demo ([#362](#)) (demo).
- Trajectory visualization ([#360](#), joint venture between [Magazino](#) and [Juraj Oršulić](#)) (demo)
- Lifelong/Multi Robot
  - Enable multi-trajectory on ROS ([#346](#), [#358](#), both contributed by [TRI](#)).

Demo • Trajectory Visualization

What landed on master? • `point_cloud_viewer`

- Bug fixes, performance improvements.
- A second, native SDL2 based viewer.
- Gamma control [#23](#)
- Demo

Current work

- Serialization of in-memory state ([#253](#))
- Pure localization ([#315](#))
- Submap deletion ([#283](#))
- Constraints visualization ([#361](#)).
- Landmarks ([#244](#))

Placeholder for other status reports

[Help wanted!](#)

Thanks!

Next Open House:
June 22, 5pm CEST (8am PST)

If you would like to present anything next meeting, please reach out to
hrapp@google.com