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](#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