Cartographer
Open House V
August 17, 2017
What landed on master? • cartographer

- Improved pose extrapolation using
  - Constant velocities (#430)
  - IMU (#434, #436)
  - Odometry (#443, #458)
- Enabled for local SLAM
  - 2D (#448)
  - 3D (#450)
- X-rays and probability grids output with draw trajectories (#421).
- Small refactorings, bug fixes and improvements.
What landed on master? • cartographer_ros

- Separate OccupancyGridNode to publish OccupancyGrid (#432, #436).
- tf is extrapolated (#451, #458, #479).
- 2D and 3D now support multiple LaserScan, MultiEchoLaserScan and PointCloud2 topics (#435).
- RViz plugin shows submap poses (#416) and IDs (#447).
- --keep_running flag for the offline node (#468).
- Bug fixes and refactorings.
Demo • Visualized trajectories

X-Ray (both lasers) and trajectory • Full size
Current work

- Odometry in the pose graph optimization (#456).
-Trimming in the middle of trajectory (#409).
-Bug fixes, refactorings, performance.
Placeholder for other status reports
Thanks!

Next Open House:
September 14, 5pm CEST (8am PST)

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