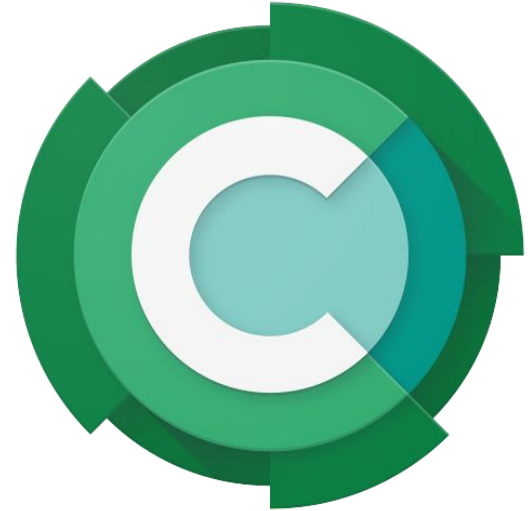


# Cartographer Open House V

August 17, 2017



# What landed on master? • cartographer

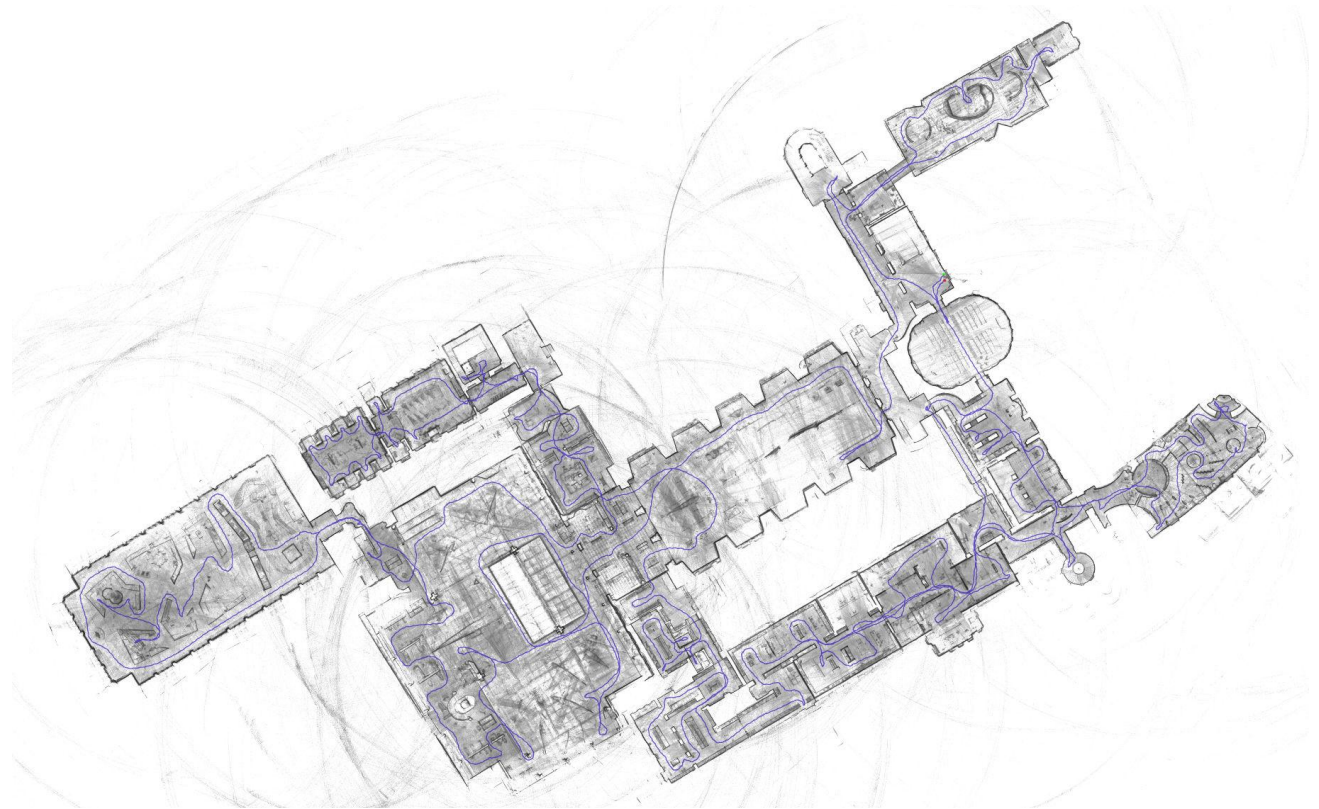
- Improved pose extrapolation using
  - Constant velocities ([#430](#))
  - IMU ([#434](#), [#436](#))
  - Odometry ([#443](#), [#458](#))
- Enabled for local SLAM
  - 2D ([#448](#))
  - 3D ([#450](#))
- X-rays and probability grids output with draw trajectories ([#421](#)).
- Small refactorings, bug 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](mailto:whess@google.com)