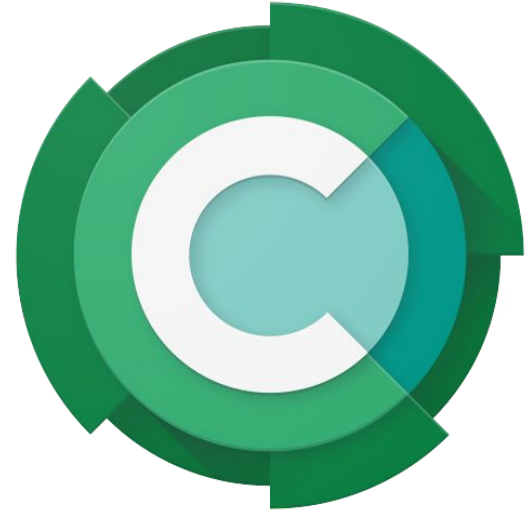


Cartographer Open House VI

September 14, 2017



What landed on master? • cartographer

- 2D SLAM: Odometry in the pose graph optimization ([#456](#)).
- 3D SLAM: Check low resolution match for loop closure ([#468](#)).
- 3D SLAM: Fixed frame pose support in pose graph ([#471](#), [#476](#), [#480](#)).
- No more range data in trajectory nodes ([#482](#), [#483](#), [#503](#)).
- Better localization performance ([#517](#)).
- Progress towards trimming for life-long mapping ([#422](#), [#472](#)).
- Bug fixes, refactorings, performance.

What landed on master? • `cartographer_ros`

- Peak memory usage output for the offline node ([#493](#)).

Current work

- Investigation of odometry quality issues, e.g. due to [#499](#).
- Visualization of low resolution grids in 3D.
- Life-long mapping, e.g. [#500](#).
- Features in 2D and 3D: Fixed frame pose in 2D, localization in 3D.
- Investigation of 3D pose graph for 2D SLAM.
- Exposing connectivity, initial pose.
- Bug fixes, refactorings, performance.

Placeholder for other status reports

Thanks!

Next Open House:
October 12, 5pm CEST (8am PST)

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