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).
Demo • Odometry support
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