Cartographer
Open House VII
October 12, 2017
What landed on master? • cartographer

- Fix odometry in the 2D pose graph optimization. (#533).
- Add trajectory trimming support to 3D. (#559)
- Add FrameIdFilteringPointsProcessor. (#566)
- Deserialize trajectory nodes. (#569)
- Add support for odometry to the 3D pose graph optimization. (#570)
- Introduces mapping::MapById in the 2D pose graph for submaps. (#578)
- Bug fixes, refactorings, performance.
What landed on master? • cartographer_ros

- Fixed ratio sensor sampling in cartographer_ros (#499).
- Demo: Unwarp each (MultiEcho)LaserScan point in the assets_writer_main. (#526)
- Demo: Visualize both high and low res slices. (#532, #506)
- Bug fixes, refactorings, performance.
Demo • Fix Odometry
Demo • Fix Odometry
Demo • Unwarping in Asset writer main (Issue 521)
Demo • Lo Hi Res Grid
Demo • Lo Hi Res Grid
Current work

- Verify Odometry fix.
- Life-long mapping, e.g. #577.
- Reuse more 3D components in 2D mapping pipeline
- Initial pose implementation.
- Bug fixes, refactorings, performance.
Placeholder for other status reports
Thanks!

Next Open House:
November 9, 5pm CEST (8am PST)

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

Next Open House:
October 26, 5pm CEST (8am PST)

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