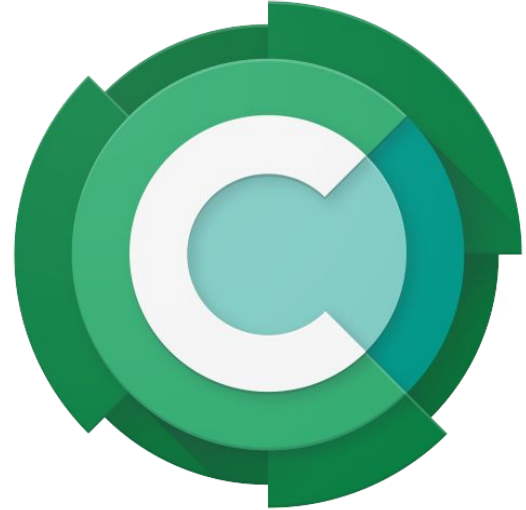


Cartographer Open House VII

October 12, 2017



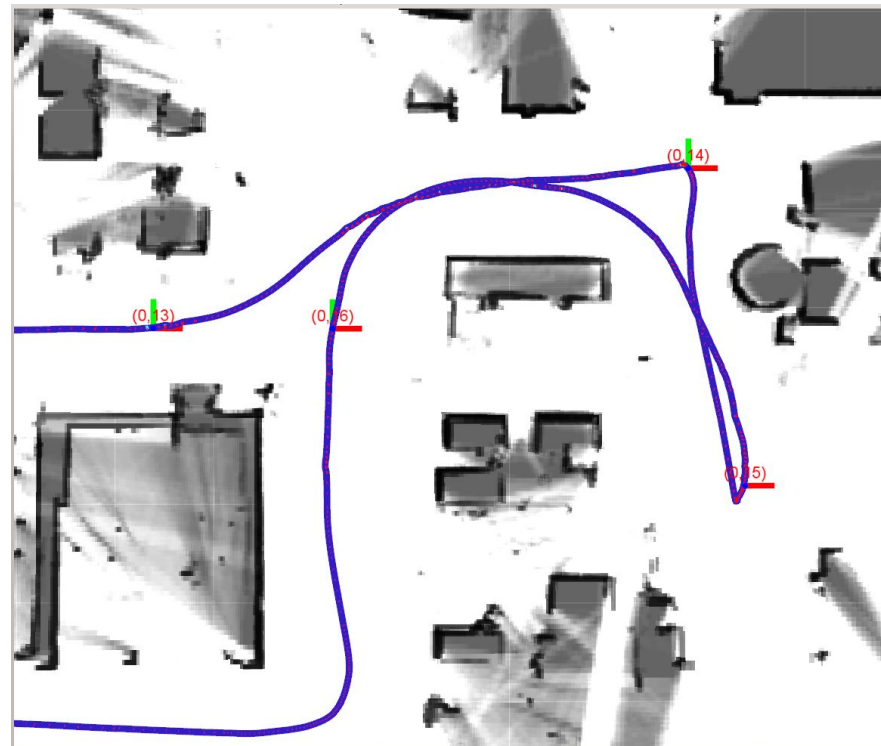
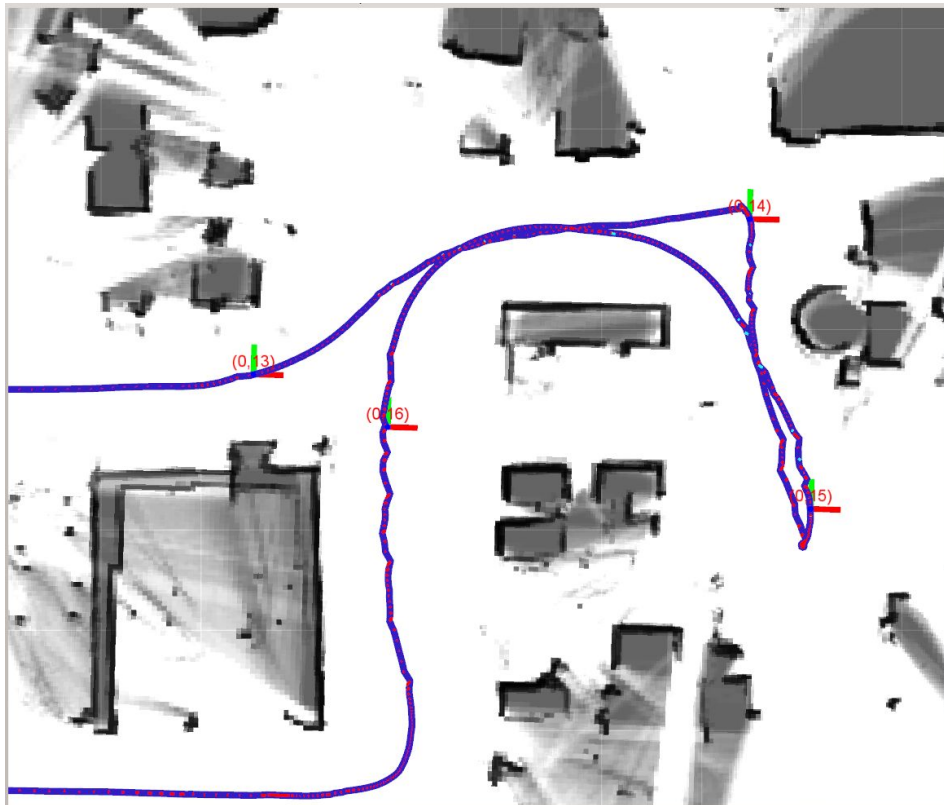
What landed on master? • cartographer

- 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.

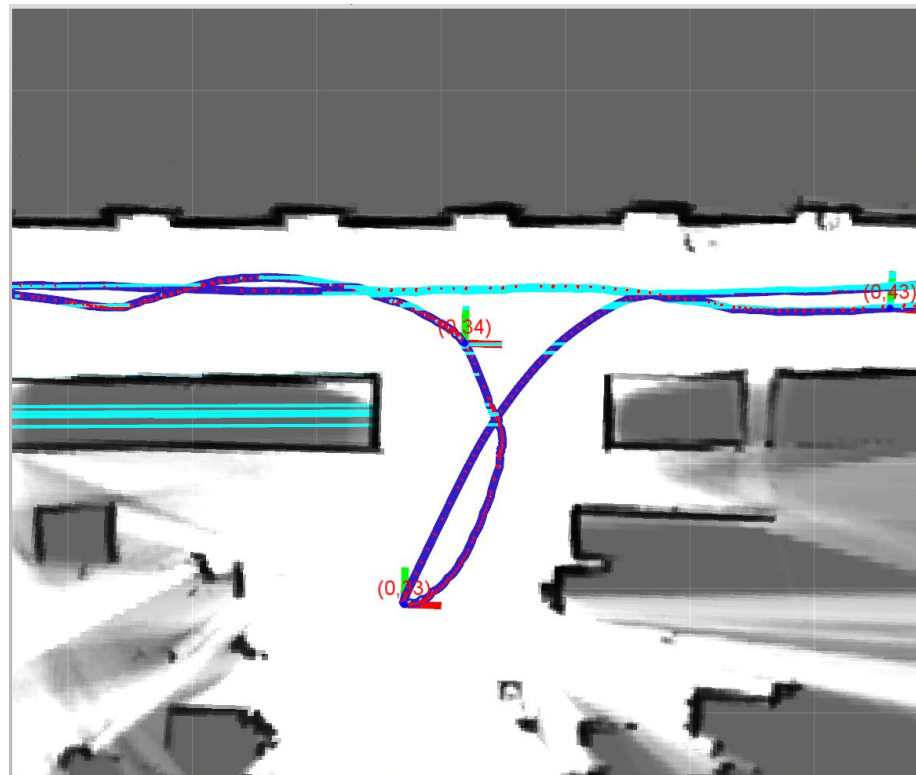
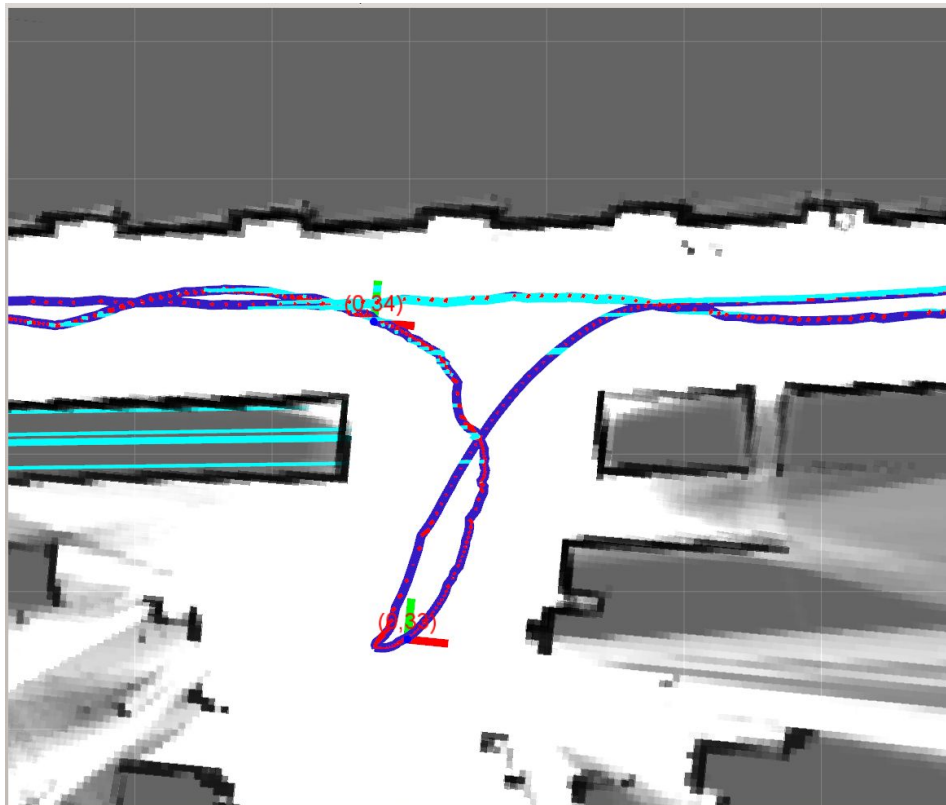
What landed on master? • cartographer_ros

- 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.

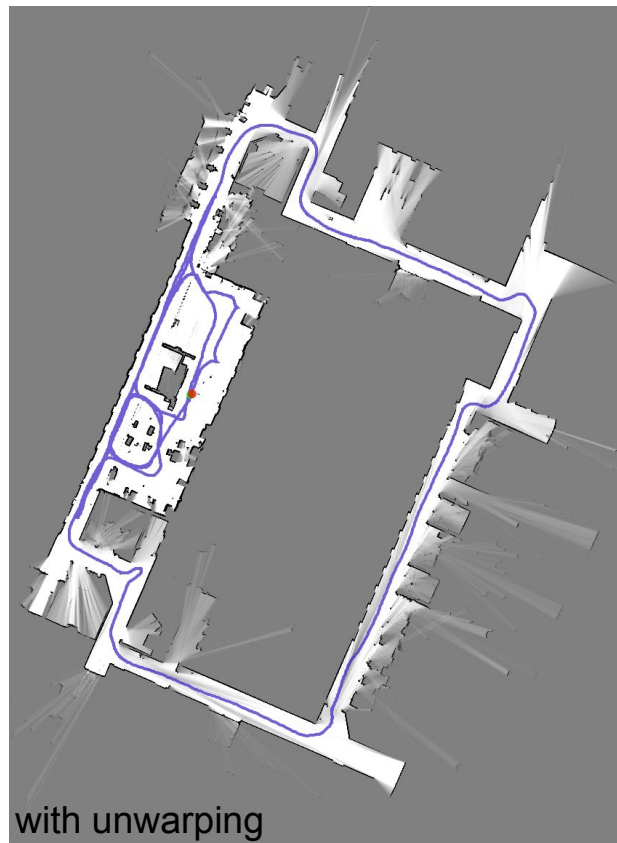
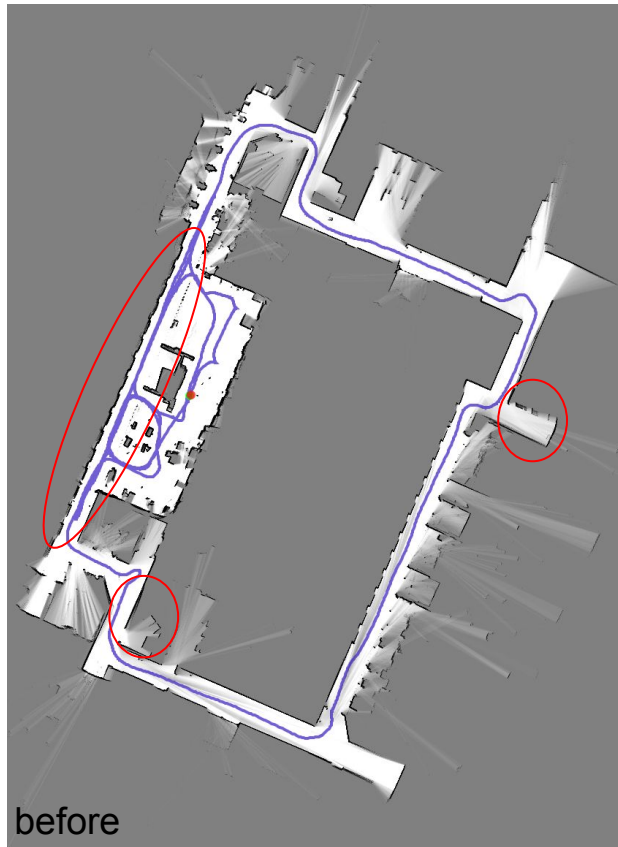
Demo • Fix Odometry



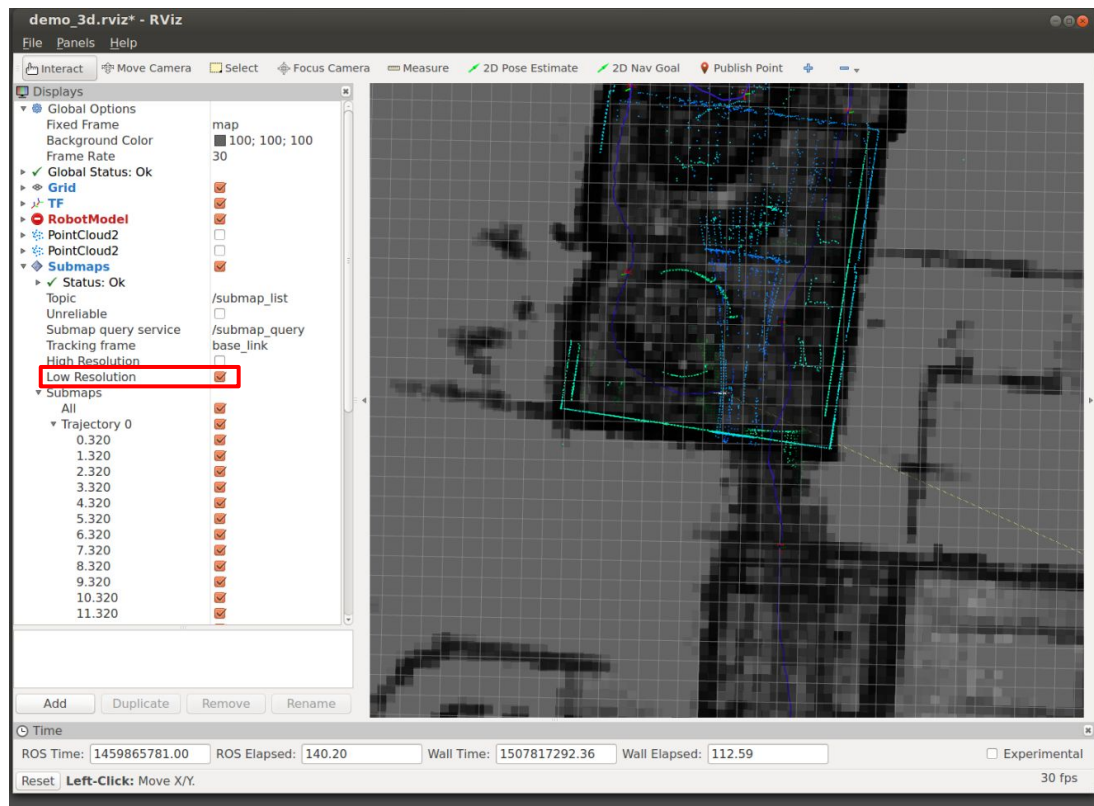
Demo • Fix Odometry



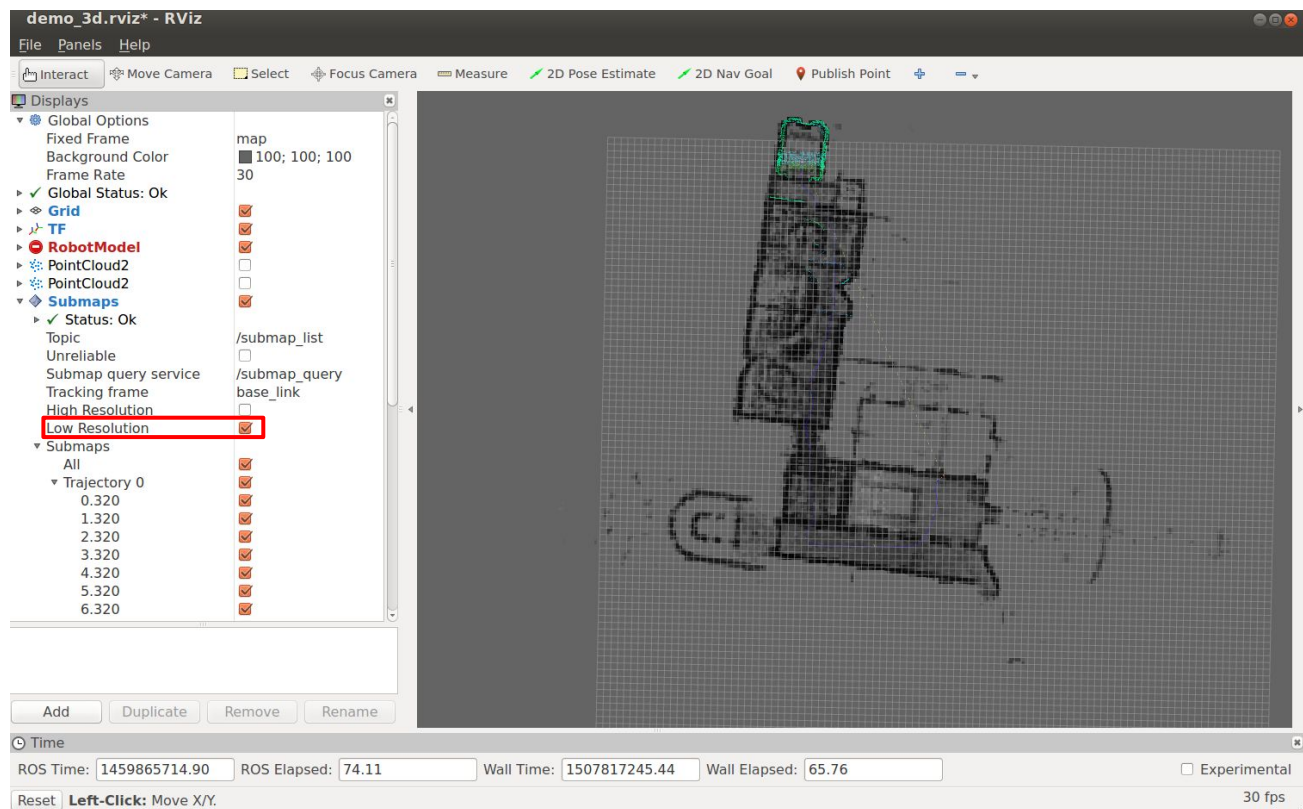
Demo • Unwarping in Asset writer main ([Issue 521](#))



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