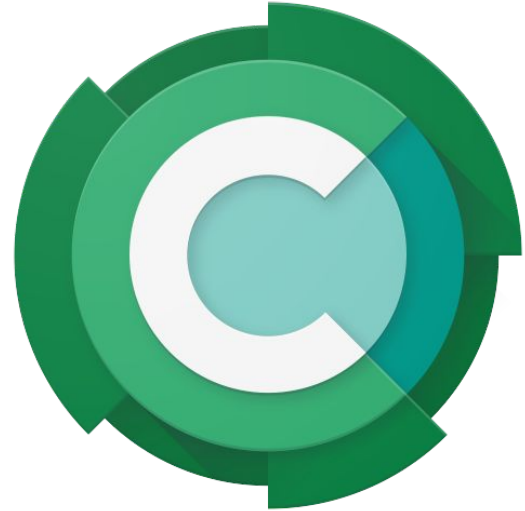


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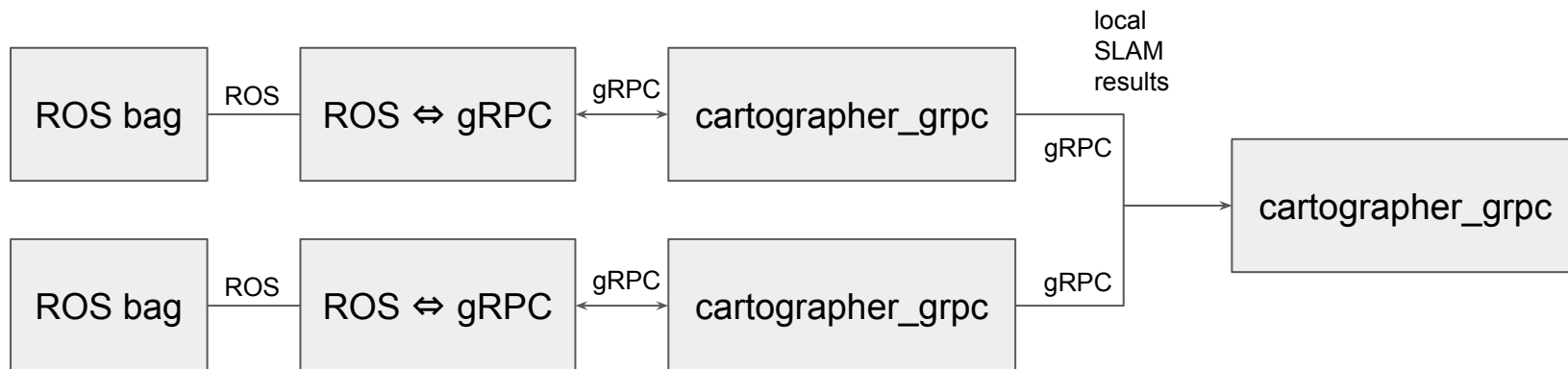
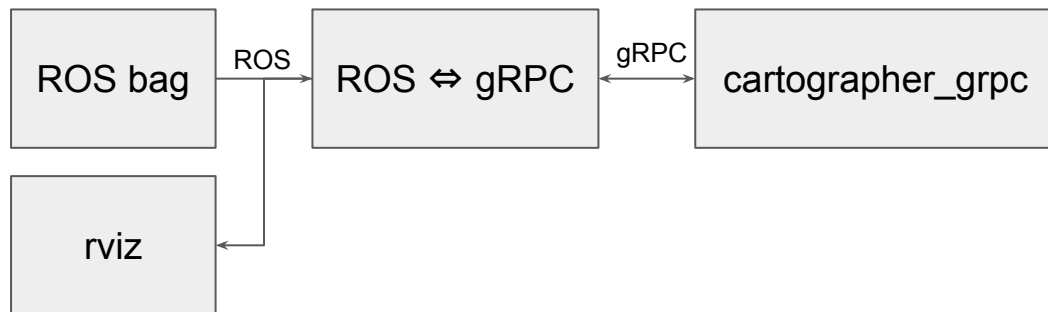
January 11, 2018



What landed on master? • cartographer

- Completed gRPC server framework [+ tests] (RFC=0002, all RPC types, event queues, thread-safety)
- Completed implementation of ROS \Leftrightarrow gRPC bridge - transparent for sensor data and rviz (RFC=0002)
- Test global 2D SLAM. ([#751](#))
- Make WaitForAllComputation wait for work queue in 3D as well ([#758](#))

Cloud-based mapping progress



What landed on master? • `cartographer_ros`

- Add ROS \leftrightarrow gRPC bridge binary (#631, #632, #643)
- Tuning guide for low latency and localization (#653)
- Wiring for `sensor_msgs::NavSatFix` (#659)

What landed on master / pending PRs? • `rfcs`

- Committed: Serve ROS map from a pbstream file
- Committed: Unify TrajectoryBuilder Interfaces.
- Committed: Introduction of PoseGraphInterface.
- Committed: nav-sat-support.
- Pending: Collator Proposal
- Pending: Document ground truth features
- Pending: Reconsider the role of odometry in the 2D optimization problem
- Pending: Improved handling of multiple trajectories and bags in the offline node (ready to commit?)

Current work

- Cloud-Based Mapping
- GPS support

Placeholder for other status reports

Thanks!

Next Open House:
January 25, 5pm CET (8am PT)

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