2024/05/18 13:57

1/1

Fusion

Fusion

Overview

The fusion node is responsible for taking the outputs of our SLAM system and the output of our object detection system, combining them, and publishing the results to the /tf topic.

Structure

Subscribes to:

- /vision/left - Object detections for left camera
- /SLAMpoints - Points for objects detected in SLAM

Publishes to:

- /tf - Global coordinates provided by SLAM combined with the labels from object detection

From:
https://robosub.eecs.wsu.edu/wiki/ - **Palouse RoboSub Technical Documentation**

Permanent link:
https://robosub.eecs.wsu.edu/wiki/cs/fusion/start?rev=1555476059

Last update: **2019/04/16 21:40**

Palouse RoboSub Technical Documentation - https://robosub.eecs.wsu.edu/wiki/