

# 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

## How to Run

Relies on the orb\_slam node and the object detection node, as well as all their dependencies. To run, execute the following command from any directory:

```
$ rosrun robosub fusion
```

From:

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

Permanent link:

<https://robosub.eecs.wsu.edu/wiki/cs/fusion/start?rev=1555476190>



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