

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>



Last update: **2019/04/16 21:43**