

# 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:

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

Permanent link:

<http://robosub-vm.eecs.wsu.edu/wiki/cs/fusion/start?rev=1555476059>



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