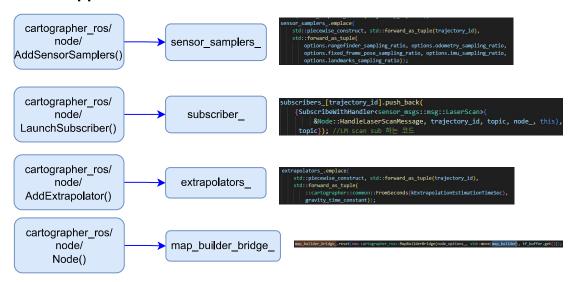
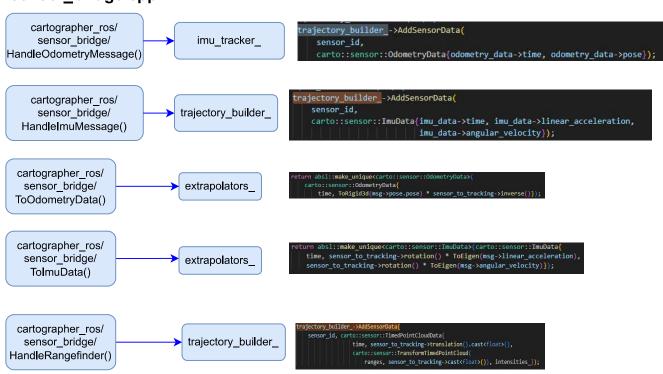


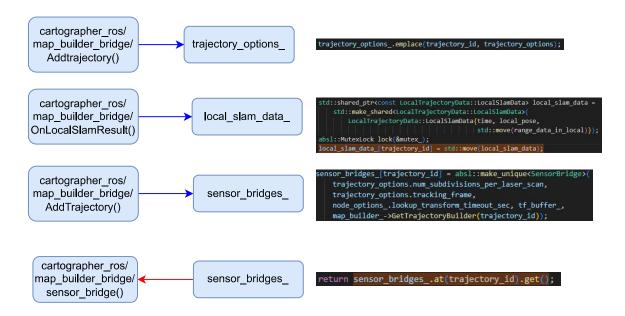
### <node.cpp>



#### <sensor\_bridge.cpp>



#### <map\_builder\_bridge.cpp>



odometry\_data\_

## <map\_builder.cc, .h>



transform::RotationQuaternionToAngleAxisVector(
odometry\_pose\_delta.rotation()) /

# <pose\_extrapolator.cc>

