List of who needs what from who

Loop Closure needs x,y,z,roll,pitch,yaw and Covariance Matrix from Pose Estimation

-Franklin S

Altitude Kalman filter – should be embedded with the pose estimation code – needs z acceleration from the IMU and height estimate from the laser range finder, along with uncertainty values for each measurement (variance in the IMU acceleration value, and variance in the LRF height estimate) – John F