



- **odom**: Odometry pose referred to odometry frame (only visual odometry is applied for ZED, visual-inertial for ZED Mini)
- **pose**: Camera pose referred to Map frame (complete data fusion algorithm is applied)
- **pose_with_covariance**: Camera pose referred to Map frame with covariance
- **path_odom**: The sequence of camera odometry poses in Map frame
- **path_map**: The sequence of camera poses in Map frame

Important: By default, RVIZ does not display odometry data correctly. Open the newly created **Odometry** object in the left list, and set **Position Tolerance** and **Angle Tolerance** to 0, and **Keep** to 1.

Launching with recorded SVO video

With the ZED, you can record and play back stereo video using the .svo file format. To record a sequence, open the [ZED Explorer](#) app and click on the REC button.

To launch the ROS wrapper with an SVO file, set an **svo_file** path launch parameter in the command line when starting the package:

ZED:

```
roslaunch zed_wrapper zed.launch svo_file:=/path
```

ZED Mini:

```
roslaunch zed_wrapper zedm.launch svo_file:=/pat
```

ZED 2:

```
roslaunch zed_wrapper zed2.launch svo_file:=/pat
```

ZED 2i:

```
roslaunch zed_wrapper zed2i.launch svo_file:=/pa
```