## cartographer数据集上评估记

## 录

数据集运行完后用ros导出运行后的轨迹,并参照官方文档中方法进行误差计算,可以得到 论文中类似结果

```
rosservice call /finish_trajectory 0
rosservice call /write_state "filename: '' " #filename指向数据集存放的
download目录中

rosrun cartographer_ros cartographer_pbstream_to_ros_map -
map_filestem=/home/sunshine/catkin_unchange/mamap -
pbstream_filename=/home/sunshine/catkin_unchange/mymap.pbstream -
resolution=0.05

cd build_isolated/cartographer/install #此時後处的目录要对应存放.pgm
.pbstream .yaml 三个文件

./cartographer_autogenerate_ground_truth -pose_graph_filename mymap.pbstream
-output_filename relations.pbstream -min_covered_distance 100 -
outlier_threshold_meters 0.15 -outlier_threshold_radians 0.02

./cartographer_compute_relations_metrics -relations_filename
relations.pbstream -pose_graph_filename mymap.pbstream #mymap是自己命名的文件
名 同上
```