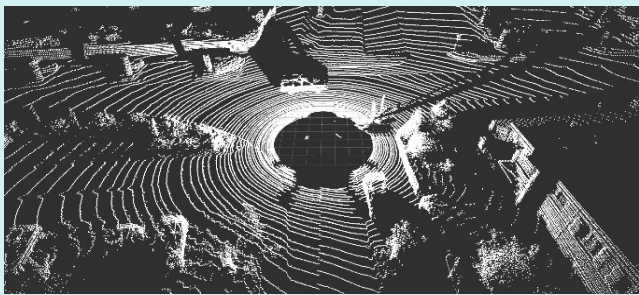
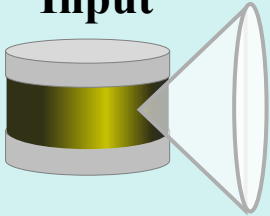


LiDAR Input



Voxelized Input
Point Cloud

Global
MAP



Map Update
([Section 5](#))

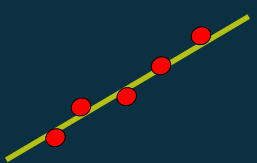
Update Feature

Local Feature Map

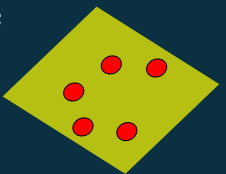
Point Cloud
to SRI

Features in SRI

Edge



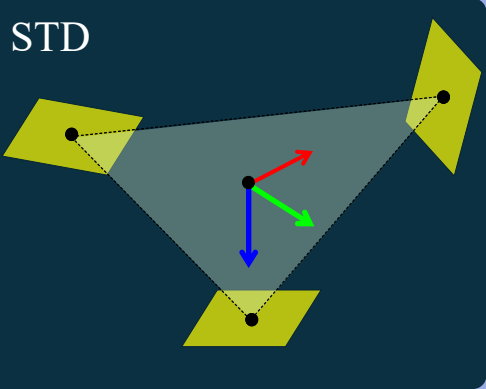
Surface



Point Cloud
Feature Extraction
([Section 3](#))

Descriptor in Point Cloud

STD



Odometry Output

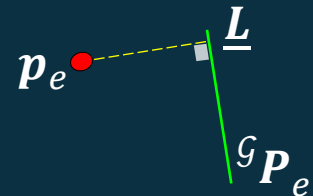
Dual-Quaternions
Optimization ([Section 4.3](#))

Dual-Quaternions
Parametrization ([Section 4.1](#))

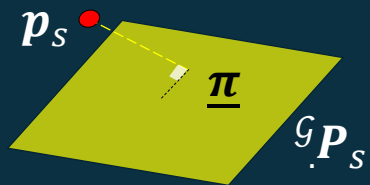
Pose Estimation
([Section 4](#))

Residuals Computation
([Section 4.2](#))

Plücker
Line



Plane



STD

