Trajectory Estimator (Localization) Basic Pipeline Development:

Pipeline:
Load the mapping result, includes landmark points and their corresponding normalized averaged descriptor values.

```
trajectory_estimator(initial pose, map)
{
    trajectory = [initial pose]
    while(next_frame)
    {
        undistort_image(next_frame)
        get_pose_from_trajectory(trajectory)
        superpoint_extraction(next_frame)
        landmark_projection(pose, map)
        landmark_association(superpoints,
                projected_landmarks)
        pose_estimate()
        trajectory.append(new pose)
    }
}
```

Top Level Unittest - Result (pass)

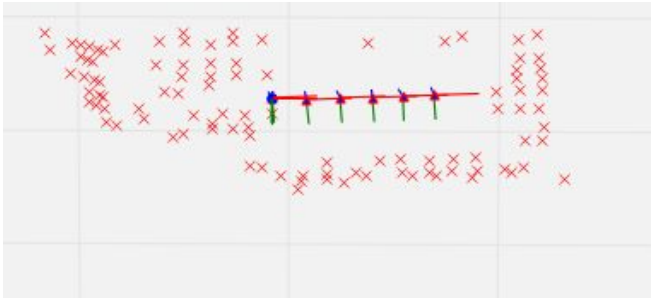

Fig 1. Along the z axis

Input with collected images - Result (wrong)

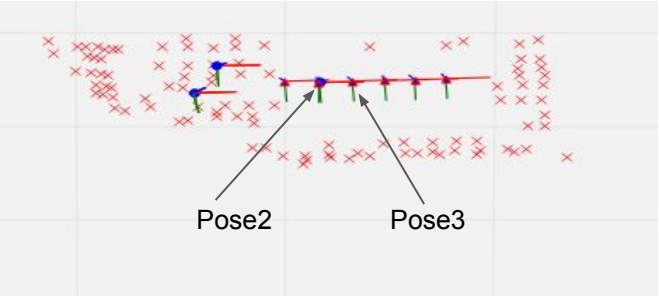

Fig 2. Along the z axis

Red crosses are landmarks. Poses (triangles at the pose origins) are poses generated through the mapping pipeline, which are the ground truths in this unittest.
Inputs:
a. The map - Landmark Object (3 lists: landmarks, descriptors, keypoints)
b. The first image from the input image set of the mapping pipeline
Output:
a. A trajectory of one pose (circle) - list

Inputs:
a. The map
b. 6 images collected along the x axis from Pose2 to Pose3.
Output:
a. A trajectory of six poses (circle)

Analysis:
a. too few landmarks
b. Parameters effect - matched feature key point distances, matched descriptors L2 distances
c. The normalized averaged descriptors may cause matching problem and required further analysis.