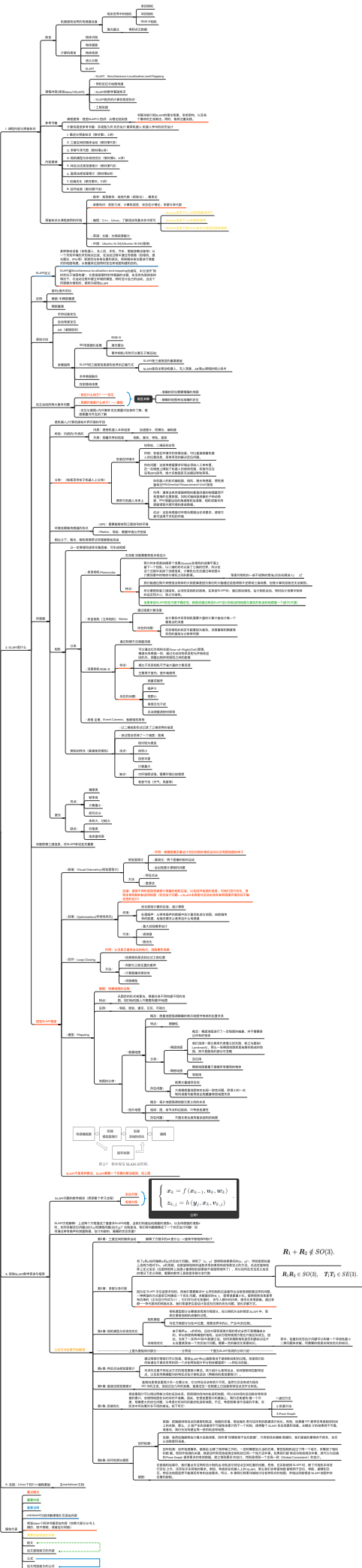


视觉SLAM理论与实践

第1章：概述与预备知识



视觉SLAM系统实现

$$\begin{cases} x_t = f(x_{t-1}, u_t, w_t) \\ z_t = h(x_t, v_t) \end{cases}$$

视觉SLAM系统性能评价

$$R_t + R_0 \notin SO(3), R_t, R_0 \in SO(3), T_t \in SE(3)$$