

Fig. 1. Top view of line mapping results of ALVIO [1], previous work [2], and UV-SLAM for MH_01_easy, MH_02_easy, MH_03_medium, MH_04_difficult, and MH_05_difficult in order from top to bottom. (a) ALVIO. (b) Previous work. (c) UV-SLAM.

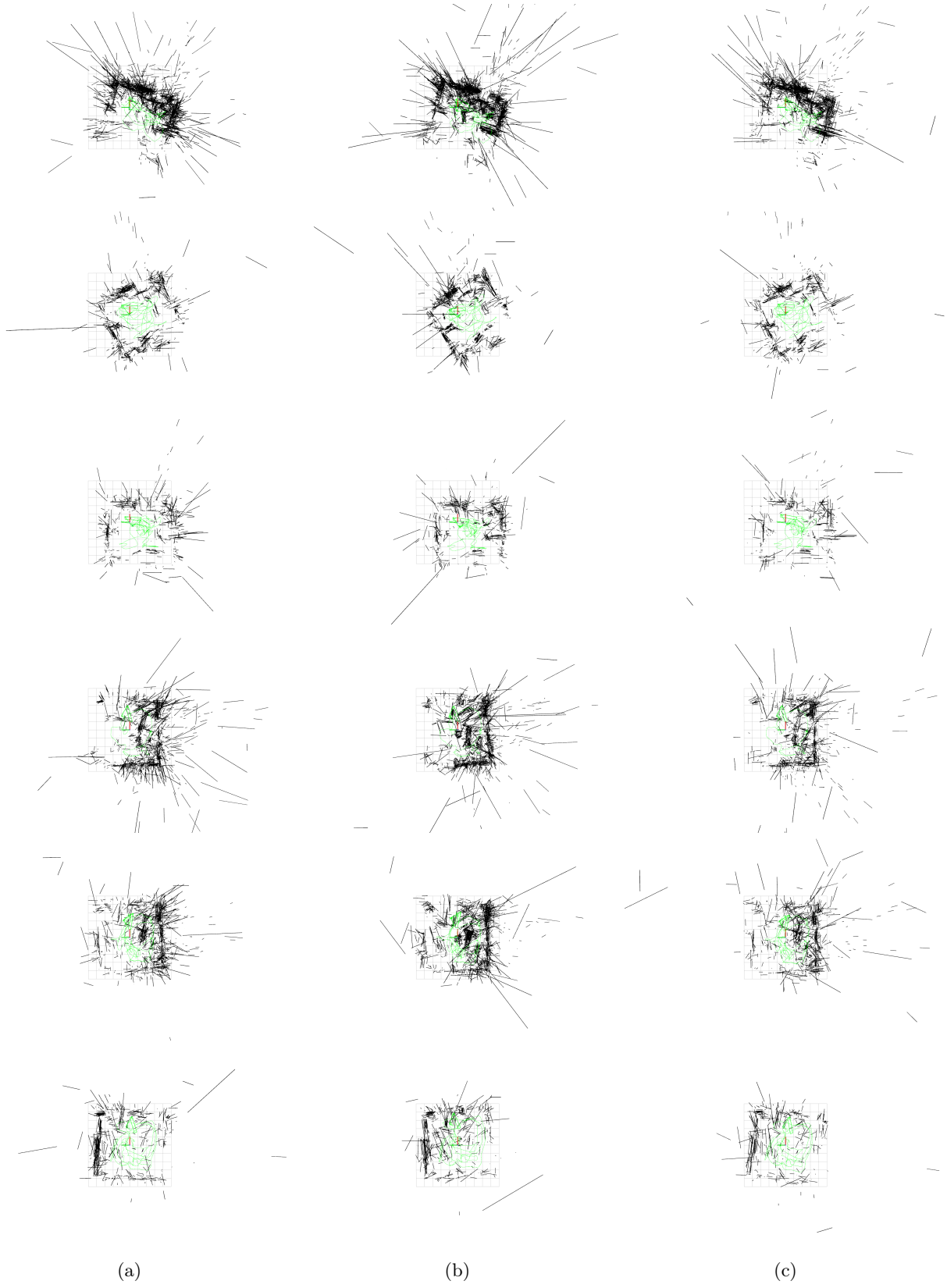


Fig. 2. Top view of line mapping results of ALVIO, previous work, and UV-SLAM for V1_01_easy, V1_02_medium, V1_03_difficult, V2_01_easy, V2_02_medium, and V2_03_difficult in order from top to bottom. (a) ALVIO. (b) Previous work. (c) UV-SLAM.

References

- [1] K. Jung, Y. Kim, H. Lim, and H. Myung, “ALVIO: Adaptive line and point feature-based visual inertial odometry for robust localization in indoor environments,” in *Proc. International Conference on Robot Intelligence Technology and Applications (RiTA)*, 2020, <https://arxiv.org/abs/2012.15008>.
- [2] H. Lim, Y. Kim, K. Jung, S. Hu, and H. Myung, “Avoiding degeneracy for monocular visual SLAM with point and line features,” in *Proc. IEEE International Conference on Robotics and Automation (ICRA)*, 2021, pp. 11 675–11 681.