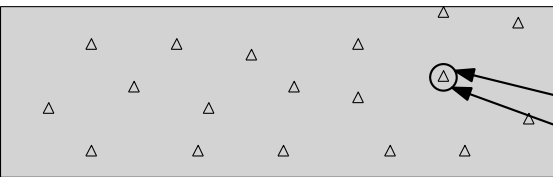
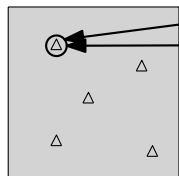


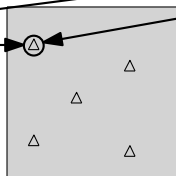
Current Frame



Omni circular image



Stereo left



Stereo right

Circular matching

3D points from stereo matches

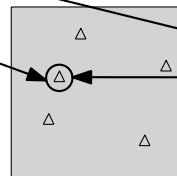
p3p - 3D stereo points, 2D omni points

R, t (metric scale)

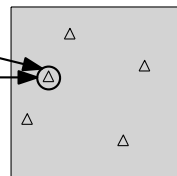
Loop Closure Frame



Omni circular image



Stereo left



Stereo right

Circular matching

3D points from stereo matches

p3p - 3D stereo points, 2D omni points

R, t (metric scale)

Weighted combination of transforms

Scaled Transform