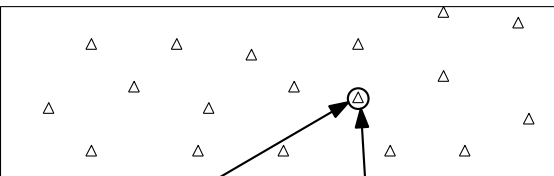
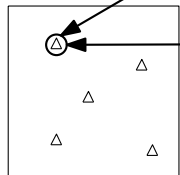


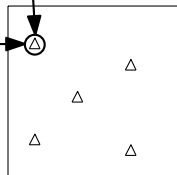
Current Frame



Omni circular image



Stereo left



Stereo right

Circular matching

3D points from stereo matches

Compare each point

Scale offsets

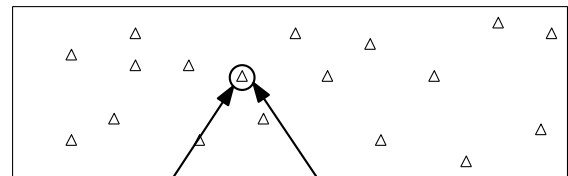
Combined scale offsets list

Robust mean

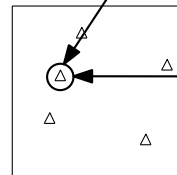
Apply scale offset to R, t

Metric scale Transform

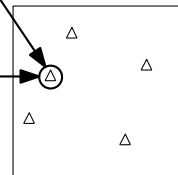
Loop Closure Frame



Omni circular image



Stereo left



Stereo right

Circular matching

3D points from stereo matches

Compare each point

Scale offsets

Feature matching

5-point algorithm

R, t (non-metric scale)

Point triangulation

Non-metric 3D points

Metric scale Transform