## Visual Odometry Pipeline

## Sandbox

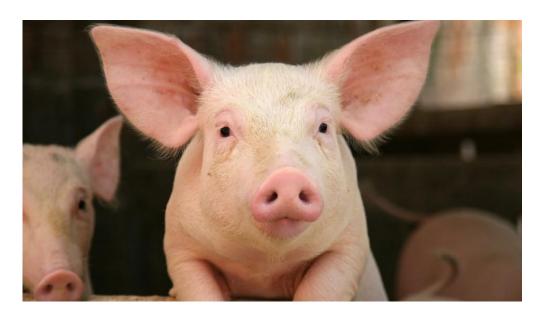


Figure 1: Pig image

## Pipeline overview

Initialization

Frame Bootstrapping

2D Correspondence search

Pose estimation

Initial point cloud triangu-lation

Continuous operation

State propagation

Pose estimation

Triangulation of new landmarks

Output odometry results

Monocular initialization Continuous Operation