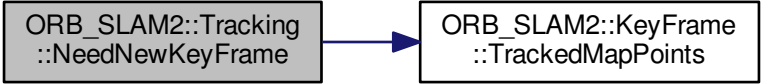


ORB\_SLAM2::Tracking  
::NeedNewKeyFrame



```
graph LR; A[ORB_SLAM2::Tracking::NeedNewKeyFrame] --> B[ORB_SLAM2::KeyFrame::TrackedMapPoints]
```

ORB\_SLAM2::KeyFrame  
::TrackedMapPoints