Motivation
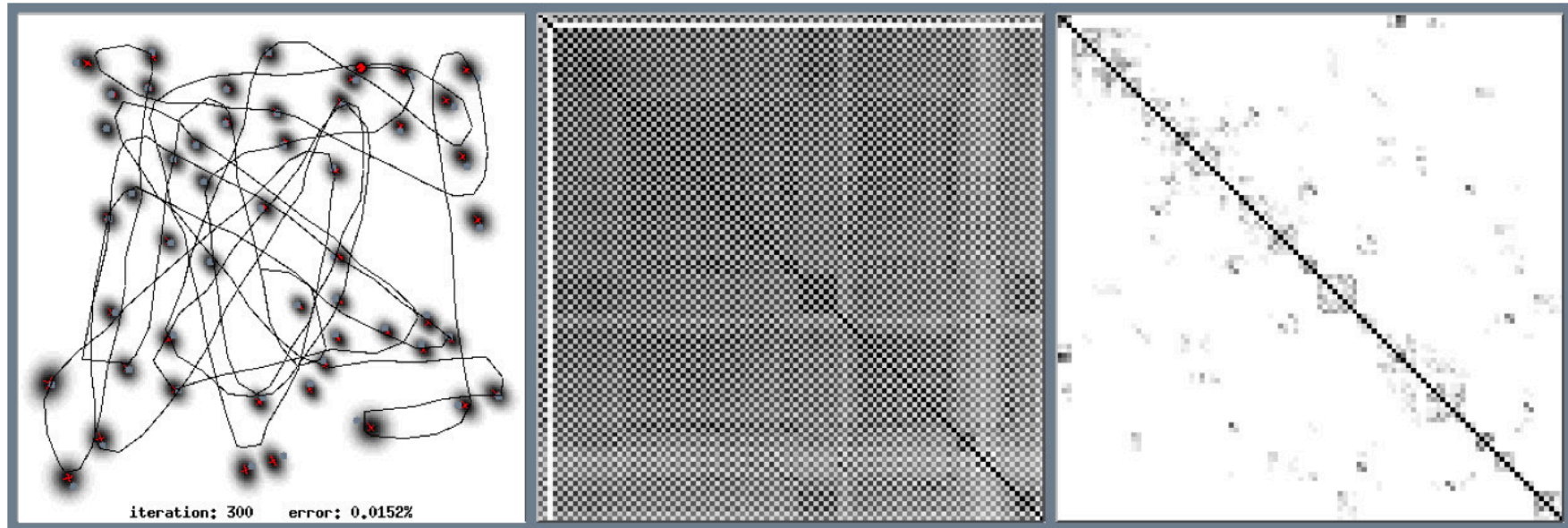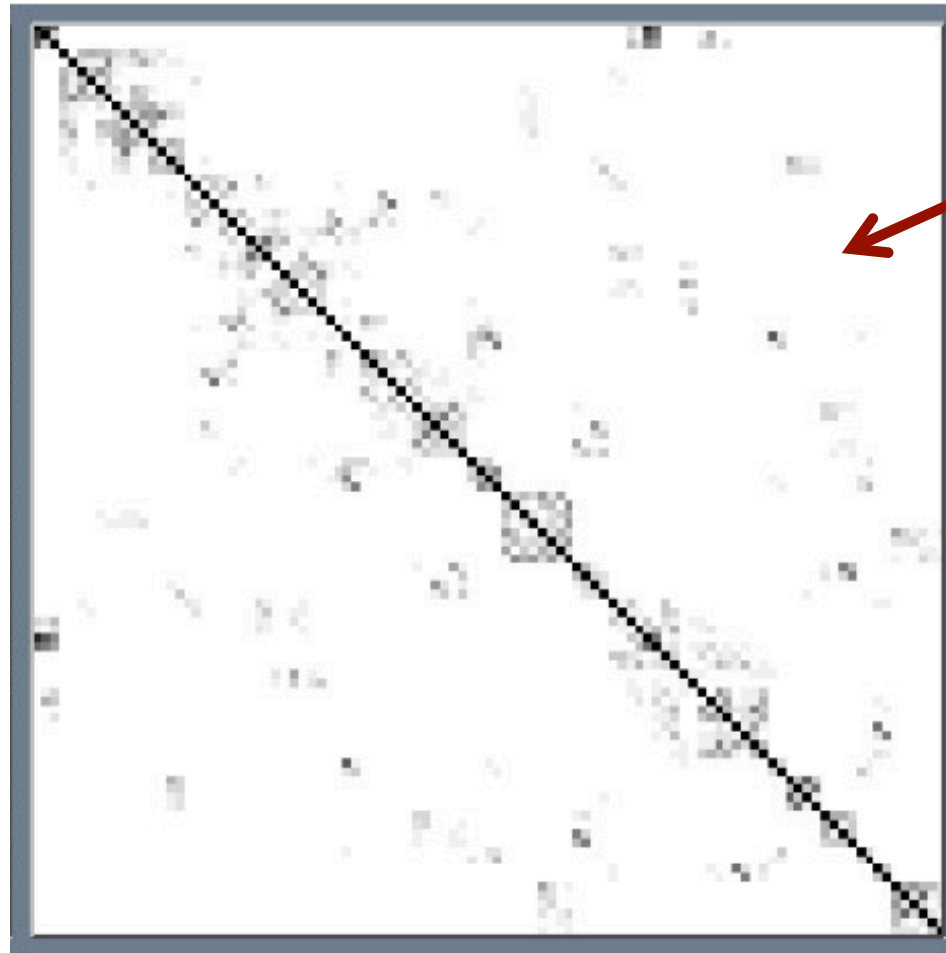

Gaussian estimate (map & pose)

normalized covariance matrix

normalized information matrix

Motivation

small but
non-zero

normalized information matrix

Most Features Have Only a Small Number of Strong Links

normalized information matrix

link

link

robot

features
active passive