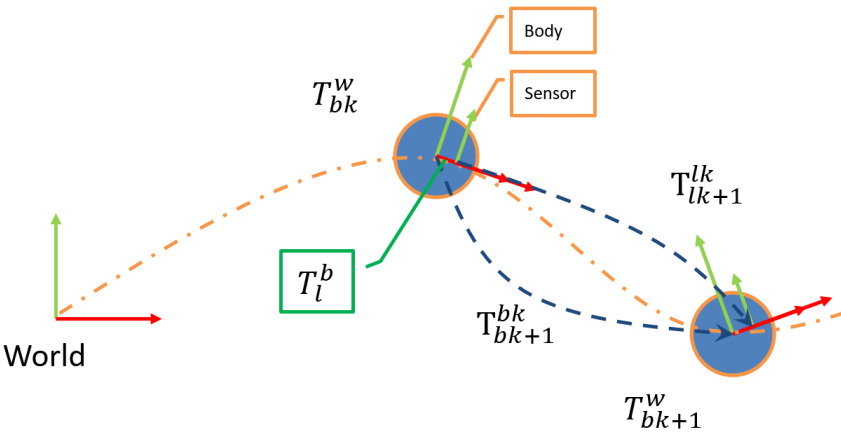
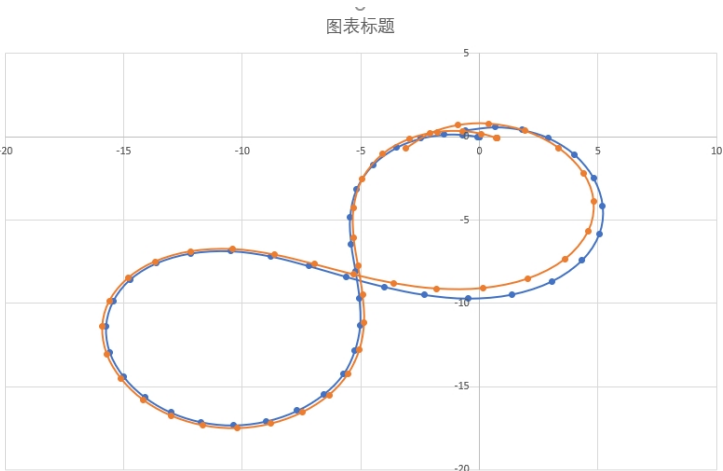


车辆运动模型外参



$$\begin{aligned} T_{lk+1}^{lk} &= T_{lk}^{w^{-1}} T_{lk+1}^w \\ &= (T_{bk}^w T_l^b)^{-1} (T_{bk+1}^w T_l^b) \\ &= T_l^{b^{-1}} T_{bk}^{w^{-1}} T_{bk+1}^w T_l^b \end{aligned}$$



$$J = \frac{1}{2} \sum_{k=1}^n \|T_{lk+1}^{\hat{lk}} - T_l^{b^{-1}} T_{bk+1}^{bk} T_l^b\|_{\Sigma^{-1}}^2$$