



Open Keyframe-based Visual-Inertial SLAM

mainThread::GPS(经纬高)

addGPS

mainThread

addImage

mainThread::位置测量

addPosition

mainThread::压差传感器

addDifferential

mainThread

addImu

mainThread::磁强计测量

addMagnetometer

CameraReceived\_

keypointMeasure\_

matchFrames\_

optimizationResult\_

displayImages\_

display()

mainThread

mainThread

frameLoop

matchLoop

optimizationLoop

publisherLoop

PoserViewer::  
stateCallBack

PoserViewer::display()

frameConsumerThread

keypointConsumerThread

imuConsumerThread

imuReceived\_

imuLoop

CallBackFunction

update pose

Push

Pop

Push

Pop

Push

Push

Push

Pop

Push

pop

CallBackFunction

update pose

Pop

Push

Pop

Push

Push

optimizationThread

visualizationThread

publisherThread 更新位姿  
显示类信息

publisherThread