



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_

Push

frameLoop

frameConsumerThread

keypointMeasure_

Push

matchLoop

keypointConsumerThread

matchFrames_

Push

optimizationLoop

optimizationThread

optimizationResult_

Push

publisherLoop

publisherThread

displayImages_

Push

visualizationLoop

visualizationThread

display()

mainThread

mainThread

publisherThread 更新位姿
显示类信息

PoserViewer::
stateCallBack

update pose

PoserViewer::display()