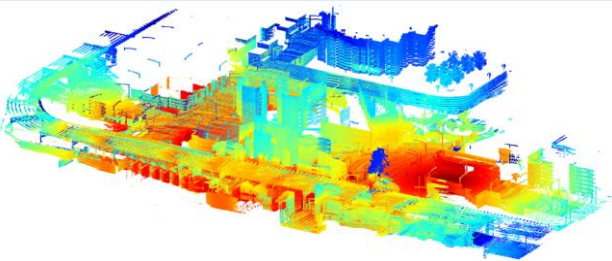
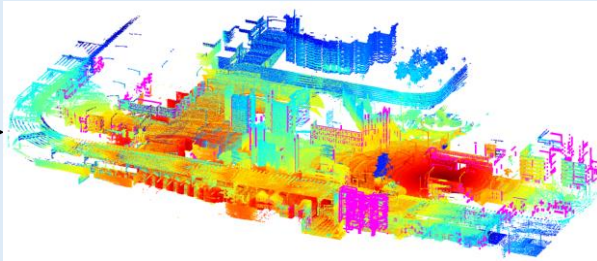


Offline

Prior point  
cloud map

3D line extraction

Light-weight  
Line Map

Online

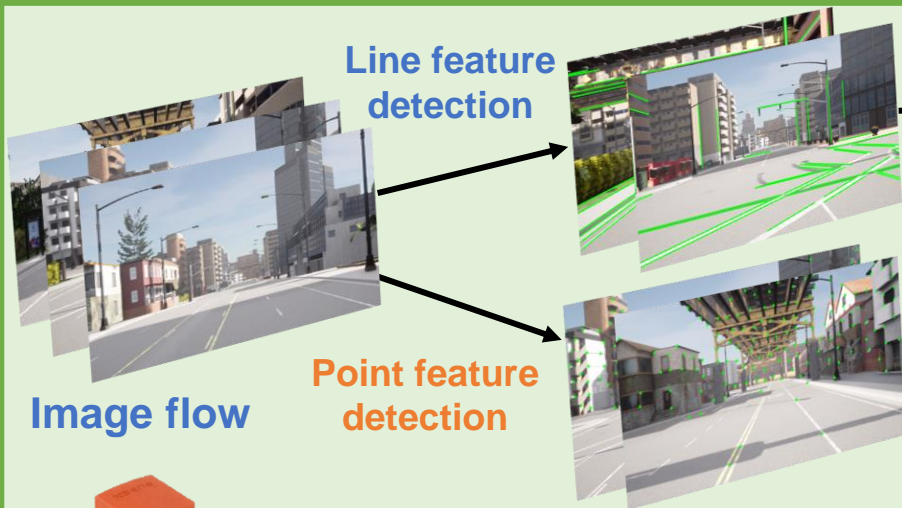
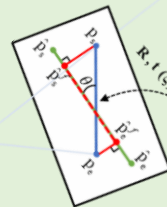


Image flow

Point feature  
detectionInitial  
guessInitial  
guess

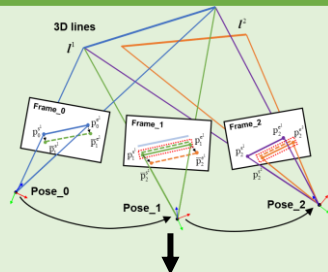
Matching

Projection



Tracking

Line factor

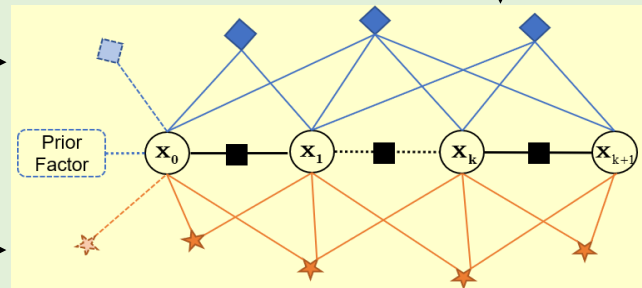


Point factor

IMU factor

Pre-integration &amp; Kinematic model

IMU Data

Factor graph  
optimizationState  
estimation