PyFactorGraph

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Classes

- class AmbiguousFGRangeMeasurement
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Variables

- frozen

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4.3.1.1 frozen

```
factor_graph.measurements.frozen
```

4.4 factor_graph.name_utils Namespace Reference

Functions

- def check_is_valid_frame_name
- def get_idx_from_frame_name
- def get_robot_char_from_frame_name
- def get_robot_char_from_number

4.4.1 Function Documentation

4.4.1.1 check_is_valid_frame_name()

```
def factor_graph.name_utils.check_is_valid_frame_name (
               frame )
```

4.4.1.2 get_idx_from_frame_name()

```
def factor_graph.name_utils.get_idx_from_frame_name (
               frame )
```

4.4.1.3 get_robot_char_from_frame_name()

```
def factor_graph.name_utils.get_robot_char_from_frame_name (
               frame )
```

4.4.1.4 get_robot_char_from_number()

```
def factor_graph.name_utils.get_robot_char_from_number (
              robot_number )
```

4.5 factor_graph.parse_factor_graph Namespace Reference

Functions

- def parse_efg_file
- def parse_pickle_file

4.5.1 Function Documentation

4.5.1.1 parse_efg_file()

```
def factor_graph.parse_factor_graph.parse_efg_file (
              filepath )
```

4.5.1.2 parse_pickle_file()

```
def factor_graph.parse_factor_graph.parse_pickle_file (
              filepath )
```

4.6 factor_graph.priors Namespace Reference

Classes

- class LandmarkPrior
- class PosePrior

Variables

- frozen

4.6.1 Variable Documentation

4.6.1.1 frozen

factor_graph.priors.frozen

4.7 factor_graph.variables Namespace Reference

Classes

- class LandmarkVariable
- class PoseVariable

Variables

- frozen

4.7.1 Variable Documentation

4.7.1.1 frozen

factor_graph.variables.frozen

Chapter 5

Class Documentation

5.1 factor_graph.measurements.AmbiguousFGRangeMeasurement Class Reference

Public Member Functions

- def check_measured_association (self, attribute, value)
- def check_true_association (self, attribute, value)
- def landmark_idx (self)
- def pose_idx (self)
- def weight (self)

Static Public Attributes

- float

5.1.1 Detailed Description

```
A range measurement

Arguments:
    var1 (str): one variable the measurement is associated with
    var2 (str): the other variable the measurement is associated with
    dist (float): The measured range
    stddev (float): The standard deviation
```

5.1.2 Member Function Documentation

5.1.2.1 check_measured_association()

```
def factor_graph.measurements.AmbiguousFGRangeMeasurement.check_measured_association (
              self,
              attribute,
              value )
```

5.1.2.2 check_true_association()

```
def factor_graph.measurements.AmbiguousFGRangeMeasurement.check_true_association (
              self,
              attribute,
              value )
```

5.1.2.3 landmark_idx()

```
def factor_graph.measurements.AmbiguousFGRangeMeasurement.landmark_idx (
              self )
```

Get the index of the landmark

5.1.2.4 pose_idx()

```
def factor_graph.measurements.AmbiguousFGRangeMeasurement.pose_idx (
              self )
```

Get the index of the pose

5.1.2.5 weight()

```
def factor_graph.measurements.AmbiguousFGRangeMeasurement.weight (
              self )
```

Get the weight of the measurement

5.1.3 Member Data Documentation

5.1.3.1 float

```
factor_graph.measurements.AmbiguousFGRangeMeasurement.float  [static]
```

The documentation for this class was generated from the following file:

- /home/alan/PyFactorGraph/factor_graph/measurements.py

5.2 factor_graph.measurements.AmbiguousPoseMeasurement Class Reference

Public Member Functions

- def covariance (self)
- def rotation_matrix (self)
- def transformation_matrix (self)
- def translation_vector (self)

Static Public Attributes

- float
- str

5.2.1 Detailed Description

```
An ambiguous odom measurement

base_pose (str): the name of the base pose which the measurement is in the
    reference frame of
measured_to_pose (str): the name of the pose the measurement thinks it is to
true_to_pose (str): the name of the pose the measurement is to
x (float): the change in x
y (float): the change in y
theta (float): the change in theta
covariance (np.ndarray): a 3x3 covariance matrix
```

5.2.2 Member Function Documentation

5.2.2.1 covariance()

```
def factor_graph.measurements.AmbiguousPoseMeasurement.covariance (
              self )
```

```
Get the covariance matrix
```

5.2.2.2 rotation_matrix()

```
def factor_graph.measurements.AmbiguousPoseMeasurement.rotation_matrix (
              self )
```

```
Get the rotation matrix for the measurement
```

5.2.2.3 transformation_matrix()

```
def factor_graph.measurements.AmbiguousPoseMeasurement.transformation_matrix (
              self )
```

Get the transformation matrix

5.2.2.4 translation_vector()

```
def factor_graph.measurements.AmbiguousPoseMeasurement.translation_vector (
              self )
```

Get the translation vector for the measurement

5.2.3 Member Data Documentation

5.2.3.1 float

```
factor_graph.measurements.AmbiguousPoseMeasurement.float  [static]
```

5.2.3.2 str

```
factor_graph.measurements.AmbiguousPoseMeasurement.str  [static]
```

The documentation for this class was generated from the following file:

- /home/alan/PyFactorGraph/factor_graph/measurements.py

5.3 factor_graph.factor_graph.FactorGraphData Class Reference

Public Member Functions

- def __str__ (self)
- def add_ambiguous_pose_measurement
- def add_ambiguous_range_measurement
- def add_landmark_prior
- def add_landmark_variable
- def add_pose_measurement
- def add_pose_prior
- def add_pose_variable

  Add data.
- def add_range_measurement
- def dimension (self)
- def dist_measurements_vect (self)
- def distance_variables_dimension (self)
- def get_ambiguous_pose_measurement_string
- def get_ambiguous_range_measurement_string
- def get_beacon_var_string
- def get_landmark_translation_variable_indices
- def get_normal_pose_measurement_string
- def get_pose_rotation_variable_indices
- def get_pose_translation_variable_indices
- def get_pose_var_string
- def get_prior_to_pin_string
- def get_range_dist_variable_indices
- def get_range_measurement_landmark
- def get_range_measurement_pose

  Accessors for the data.
- def get_range_measurement_string
- def measurements_weight_vect (self)
- def num_landmarks (self)
- def num_pose_measurements (self)
- def num_poses (self)
- def num_range_measurements (self)
- def num_total_measurements (self)
- def num_translations (self)
- def poses_and_landmarks_dimension (self)
- def save_to_file
- def sum_weighted_measurements_squared (self)
- def true_values_vector (self)
- def weighted_dist_measurements_vect (self)

Static Public Attributes

- covar_info
- cur_id
- d
- default
- del_theta
- del_x
- del_y

- factory
- file_writer
- int
- landmark_idx
- landmark_name
- line
- measure_id
- measured_beacon_id
- measured_robot_id
- offset
- pose_idx
- range_factor_type
- robot_id
- start
- stop
- true_beacon_id
- true_measure_id
- true_robot_id

5.3.1 Detailed Description

```
Just a container for the data in a FactorGraph. Only considers standard
gaussian measurements.

Args:
    pose_variables (List[PoseVariable]): a list of the pose variables
    landmark_variables (List[LandmarkVariable]): a list of the landmarks
    pose_measurements (List[PoseMeasurement]): a list of odom
        measurements
    ambiguous_pose_measurements (List[AmbiguousPoseMeasurement]): a list of
        ambiguous pose measurements
    range_measurements (List[FGRangeMeasurement]): a list of range
        measurements
    ambiguous_range_measurements (List[AmbiguousFGRangeMeasurement]): a list
        of ambiguous range measurements
    pose_priors (List[PosePrior]): a list of the pose priors
    landmark_priors (List[LandmarkPrior]): a list of the landmark priors
```

5.3.2 Member Function Documentation

5.3.2.1 __str__()

```
def factor_graph.factor_graph.FactorGraphData.__str__ (
             self )
```

5.3.2.2 add_ambiguous_pose_measurement()

```
def factor_graph.factor_graph.FactorGraphData.add_ambiguous_pose_measurement (
             self,
             measure )
```

5.3.2.3 add_ambiguous_range_measurement()

```
def factor_graph.factor_graph.FactorGraphData.add_ambiguous_range_measurement (
              self,
              measure )
```

5.3.2.4 add_landmark_prior()

```
def factor_graph.factor_graph.FactorGraphData.add_landmark_prior (
              self,
              landmark_prior )
```

5.3.2.5 add_landmark_variable()

```
def factor_graph.factor_graph.FactorGraphData.add_landmark_variable (
              self,
              landmark_var )
```

5.3.2.6 add_pose_measurement()

```
def factor_graph.factor_graph.FactorGraphData.add_pose_measurement (
              self,
              odom_meas )
```

5.3.2.7 add_pose_prior()

```
def factor_graph.factor_graph.FactorGraphData.add_pose_prior (
              self,
              pose_prior )
```

5.3.2.8 add_pose_variable()

```
def factor_graph.factor_graph.FactorGraphData.add_pose_variable (
              self,
              pose_var )
```

Add data.

5.3.2.9 add_range_measurement()

```
def factor_graph.factor_graph.FactorGraphData.add_range_measurement (
              self,
              range_meas )
```

5.3.2.10 dimension()

```
def factor_graph.factor_graph.FactorGraphData.dimension (
              self )
```

5.3.2.11 dist_measurements_vect()

```
def factor_graph.factor_graph.FactorGraphData.dist_measurements_vect (
              self,
              np,
              ndarray )
```

```
Get a vector of the distance measurements

Returns:
    np.ndarray: a vector of the distance measurements
```

5.3.2.12 distance_variables_dimension()

```
def factor_graph.factor_graph.FactorGraphData.distance_variables_dimension (
              self )
```

5.3.2.13 get_ambiguous_pose_measurement_string()

```
def factor_graph.factor_graph.FactorGraphData.get_ambiguous_pose_measurement_string (
              pose_measure )
```

5.3.2.14 get_ambiguous_range_measurement_string()

```
def factor_graph.factor_graph.FactorGraphData.get_ambiguous_range_measurement_string (
              range_measure )
```

5.3.2.15 get_beacon_var_string()

```
def factor_graph.factor_graph.FactorGraphData.get_beacon_var_string (
              beacon )
```

5.3.2.16 get_landmark_translation_variable_indices()

```
def factor_graph.factor_graph.FactorGraphData.get_landmark_translation_variable_indices (
              self,
              landmark )
```

5.3.2.17 get_normal_pose_measurement_string()

```
def factor_graph.factor_graph.FactorGraphData.get_normal_pose_measurement_string (
              pose_measure )
```

5.3.2.18 get_pose_rotation_variable_indices()

```
def factor_graph.factor_graph.FactorGraphData.get_pose_rotation_variable_indices (
              self,
              pose )
```

5.3.2.19 get_pose_translation_variable_indices()

```
def factor_graph.factor_graph.FactorGraphData.get_pose_translation_variable_indices (
              self,
              pose )
```

5.3.2.20 get_pose_var_string()

```
def factor_graph.factor_graph.FactorGraphData.get_pose_var_string (
              pose )
```

5.3.2.21 get_prior_to_pin_string()

```
def factor_graph.factor_graph.FactorGraphData.get_prior_to_pin_string (
              prior )
```

5.3.2.22 get_range_dist_variable_indices()

```
def factor_graph.factor_graph.FactorGraphData.get_range_dist_variable_indices (
              self,
              measurement )
```

5.3.2.23 get_range_measurement_landmark()

```
def factor_graph.factor_graph.FactorGraphData.get_range_measurement_landmark (
              self,
              measure )
```

5.3.2.24 get_range_measurement_pose()

```
def factor_graph.factor_graph.FactorGraphData.get_range_measurement_pose (
              self,
              measure )
```

Accessors for the data.

5.3.2.25 get_range_measurement_string()

```
def factor_graph.factor_graph.FactorGraphData.get_range_measurement_string (
              range_measure )
```

5.3.2.26 measurements_weight_vect()

```
def factor_graph.factor_graph.FactorGraphData.measurements_weight_vect (
              self,
              np,
              ndarray )
```

Get the weights of the measurements

5.3.2.27 num_landmarks()

```
def factor_graph.factor_graph.FactorGraphData.num_landmarks (
              self )
```

5.3.2.28 num_pose_measurements()

```
def factor_graph.factor_graph.FactorGraphData.num_pose_measurements (
              self )
```

5.3.2.29 num_poses()

```
def factor_graph.factor_graph.FactorGraphData.num_poses (
              self )
```

5.3.2.30 num_range_measurements()

```
def factor_graph.factor_graph.FactorGraphData.num_range_measurements (
              self )
```

5.3.2.31 num_total_measurements()

```
def factor_graph.factor_graph.FactorGraphData.num_total_measurements (
              self )
```

5.3.2.32 num_translations()

```
def factor_graph.factor_graph.FactorGraphData.num_translations (
              self )
```

5.3.2.33 poses_and_landmarks_dimension()

```
def factor_graph.factor_graph.FactorGraphData.poses_and_landmarks_dimension (
              self )
```

5.3.2.34 save_to_file()

```
def factor_graph.factor_graph.FactorGraphData.save_to_file (
              self,
              filepath )
```

5.3.2.35 sum_weighted_measurements_squared()

```
def factor_graph.factor_graph.FactorGraphData.sum_weighted_measurements_squared (
              self,
              float )
```

Get the sum of the squared weighted measurements

5.3.2.36 true_values_vector()

```
def factor_graph.factor_graph.FactorGraphData.true_values_vector (
              self,
              np,
              ndarray )
```

returns the true values in a vectorized form

5.3.2.37 weighted_dist_measurements_vect()

```
def factor_graph.factor_graph.FactorGraphData.weighted_dist_measurements_vect (
              self,
              np,
              ndarray )
```

Get of the distance measurements weighted by their precision

5.3.3 Member Data Documentation

5.3.3.1 covar_info

```
factor_graph.factor_graph.FactorGraphData.covar_info  [static]
```

5.3.3.2 cur_id

factor_graph.factor_graph.FactorGraphData.cur_id [static]

5.3.3.3 d

factor_graph.factor_graph.FactorGraphData.d [static]

5.3.3.4 default

factor_graph.factor_graph.FactorGraphData.default [static]

5.3.3.5 del_theta

factor_graph.factor_graph.FactorGraphData.del_theta [static]

5.3.3.6 del_x

factor_graph.factor_graph.FactorGraphData.del_x [static]

5.3.3.7 del_y

factor_graph.factor_graph.FactorGraphData.del_y [static]

5.3.3.8 factory

factor_graph.factor_graph.FactorGraphData.factory [static]

5.3.3.9 file_writer

factor_graph.factor_graph.FactorGraphData.file_writer [static]

5.3.3.10 int

factor_graph.factor_graph.FactorGraphData.int [static]

5.3.3.11 landmark_idx

factor_graph.factor_graph.FactorGraphData.landmark_idx [static]

5.3.3.12 landmark_name

factor_graph.factor_graph.FactorGraphData.landmark_name [static]

5.3.3.13 line

factor_graph.factor_graph.FactorGraphData.line [static]

5.3.3.14 measure_id

factor_graph.factor_graph.FactorGraphData.measure_id [static]

5.3.3.15 measured_beacon_id

factor_graph.factor_graph.FactorGraphData.measured_beacon_id [static]

5.3.3.16 measured_robot_id

factor_graph.factor_graph.FactorGraphData.measured_robot_id [static]

5.3.3.17 offset

factor_graph.factor_graph.FactorGraphData.offset [static]

5.3.3.18 pose_idx

factor_graph.factor_graph.FactorGraphData.pose_idx [static]

5.3.3.19 range_factor_type

factor_graph.factor_graph.FactorGraphData.range_factor_type [static]

5.3.3.20 robot_id

factor_graph.factor_graph.FactorGraphData.robot_id [static]

5.3.3.21 start

factor_graph.factor_graph.FactorGraphData.start [static]

5.3.3.22 stop

factor_graph.factor_graph.FactorGraphData.stop [static]

5.3.3.23 true_beacon_id

factor_graph.factor_graph.FactorGraphData.true_beacon_id [static]

5.3.3.24 true_measure_id

factor_graph.factor_graph.FactorGraphData.true_measure_id [static]

5.3.3.25 true_robot_id

```
factor_graph.factor_graph.FactorGraphData.true_robot_id  [static]
```

The documentation for this class was generated from the following file:

- /home/alan/PyFactorGraph/factor_graph/factor_graph.py

5.4 factor_graph.measurements.FGRangeMeasurement Class Reference

Public Member Functions

- def check_association (self, attribute, value)
- def landmark_idx (self)
- def pose_idx (self)
- def weight (self)

Static Public Attributes

- float

5.4.1 Detailed Description

```
A range measurement

Arguments:
    association (Tuple[str]): the data associations of the measurement
    dist (float): The measured range
    stddev (float): The standard deviation
```

5.4.2 Member Function Documentation

5.4.2.1 check_association()

```
def factor_graph.measurements.FGRangeMeasurement.check_association (
             self,
             attribute,
             value )
```

5.4.2.2 landmark_idx()

```
def factor_graph.measurements.FGRangeMeasurement.landmark_idx (
              self )
```

Get the index of the landmark

5.4.2.3 pose_idx()

```
def factor_graph.measurements.FGRangeMeasurement.pose_idx (
              self )
```

Get the index of the pose

5.4.2.4 weight()

```
def factor_graph.measurements.FGRangeMeasurement.weight (
              self )
```

Get the weight of the measurement

5.4.3 Member Data Documentation

5.4.3.1 float

```
factor_graph.measurements.FGRangeMeasurement.float  [static]
```

The documentation for this class was generated from the following file:

- /home/alan/PyFactorGraph/factor_graph/measurements.py

5.5 factor_graph.priors.LandmarkPrior Class Reference

Static Public Attributes

- ndarray
- str

5.5.1 Detailed Description

```
A prior on the landmark

Arguments:
    name (str): the name of the landmark variable
    position (Tuple[float, float]): the prior of the position
    covariance (np.ndarray): the covariance of the prior
```

5.5.2 Member Data Documentation

5.5.2.1 ndarray

```
factor_graph.priors.LandmarkPrior.ndarray  [static]
```

5.5.2.2 str

```
factor_graph.priors.LandmarkPrior.str  [static]
```

The documentation for this class was generated from the following file:

- /home/alan/PyFactorGraph/factor_graph/priors.py

5.6 factor_graph.variables.LandmarkVariable Class Reference

Public Member Functions

- def true_x (self)
- def true_y (self)

Static Public Attributes

- str

5.6.1 Detailed Description

```
A variable which is a landmark

Arguments:
    name (str): the name of the variable
    true_position (Tuple[float, float]): the true position of the landmark
```

5.6.2 Member Function Documentation

5.6.2.1 true_x()

```
def factor_graph.variables.LandmarkVariable.true_x (
              self )
```

5.6.2.2 true_y()

```
def factor_graph.variables.LandmarkVariable.true_y (
              self )
```

5.6.3 Member Data Documentation

5.6.3.1 str

```
factor_graph.variables.LandmarkVariable.str  [static]
```

The documentation for this class was generated from the following file:

- /home/alan/PyFactorGraph/factor_graph/variables.py

5.7 factor_graph.measurements.PoseMeasurement Class Reference

Public Member Functions

- def base_pose_idx (self)
- def covariance (self)
- def rotation_matrix (self)
- def to_pose_idx (self)
- def transformation_matrix (self)
- def translation_vector (self)

Static Public Attributes

- float
- str

5.7.1 Detailed Description

```
An pose measurement

base_pose (str): the name of the base pose which the measurement is in the
    reference frame of
local_pose (str): the name of the pose the measurement is to
x (float): the change in x coordinate of the measurement
y (float): the change in y coordinate of the measurement
theta (float): the change in theta
covariance (np.ndarray): a 3x3 covariance matrix
```

5.7.2 Member Function Documentation

5.7.2.1 base_pose_idx()

```
def factor_graph.measurements.PoseMeasurement.base_pose_idx (
              self,
              int )

Get the index of the base pose
```

5.7.2.2 covariance()

```
def factor_graph.measurements.PoseMeasurement.covariance (
              self )

Get the covariance matrix
```

5.7.2.3 rotation_matrix()

```
def factor_graph.measurements.PoseMeasurement.rotation_matrix (
              self )

Get the rotation matrix for the measurement
```

5.7.2.4 to_pose_idx()

```
def factor_graph.measurements.PoseMeasurement.to_pose_idx (
              self,
              int )
```

Get the index of the to pose

5.7.2.5 transformation_matrix()

```
def factor_graph.measurements.PoseMeasurement.transformation_matrix (
              self )
```

Get the transformation matrix

5.7.2.6 translation_vector()

```
def factor_graph.measurements.PoseMeasurement.translation_vector (
              self )
```

Get the translation vector for the measurement

5.7.3 Member Data Documentation

5.7.3.1 float

```
factor_graph.measurements.PoseMeasurement.float  [static]
```

5.7.3.2 str

```
factor_graph.measurements.PoseMeasurement.str  [static]
```

The documentation for this class was generated from the following file:

- /home/alan/PyFactorGraph/factor_graph/measurements.py

5.8 factor_graph.priors.PosePrior Class Reference

Public Member Functions

- def x (self)
- def y (self)

Static Public Attributes

- float
- ndarray
- str

5.8.1 Detailed Description

```
A prior on the robot pose

Arguments:
    name (str): the name of the pose variable
    position (Tuple[float, float]): the prior of the position
    theta (float): the prior of the theta
    covariance (np.ndarray): the covariance of the prior
```

5.8.2 Member Function Documentation

5.8.2.1 x()

```
def factor_graph.priors.PosePrior.x (
              self )
```

5.8.2.2 y()

```
def factor_graph.priors.PosePrior.y (
              self )
```

5.8.3 Member Data Documentation

5.8.3.1 float

```
factor_graph.priors.PosePrior.float  [static]
```

5.8.3.2 ndarray

```
factor_graph.priors.PosePrior.ndarray  [static]
```

5.8.3.3 str

```
factor_graph.priors.PosePrior.str  [static]
```

The documentation for this class was generated from the following file:

- /home/alan/PyFactorGraph/factor_graph/priors.py

5.9 factor_graph.variables.PoseVariable Class Reference

Public Member Functions

- def rotation_matrix (self)
- def true_x (self)
- def true_y (self)

Static Public Attributes

- float
- str

5.9.1 Detailed Description

```
A variable which is a robot pose

Arguments:
    name (str): the name of the variable (defines the frame)
    true_position (Tuple[float, float]): the true position of the robot
    true_theta (float): the true orientation of the robot
```

5.9.2 Member Function Documentation

5.9.2.1 rotation_matrix()

```
def factor_graph.variables.PoseVariable.rotation_matrix (
              self )
```

```
Get the rotation matrix for the measurement
```

5.9.2.2 true_x()

```
def factor_graph.variables.PoseVariable.true_x (
              self )
```

5.9.2.3 true_y()

```
def factor_graph.variables.PoseVariable.true_y (
              self )
```

5.9.3 Member Data Documentation

5.9.3.1 float

```
factor_graph.variables.PoseVariable.float  [static]
```

5.9.3.2 str

```
factor_graph.variables.PoseVariable.str  [static]
```

The documentation for this class was generated from the following file:

- /home/alan/PyFactorGraph/factor_graph/variables.py

Chapter 6

File Documentation

6.1 /home/alan/PyFactorGraph/factor_graph/__init__.py File Reference

Namespaces

- factor_graph

6.2 /home/alan/PyFactorGraph/factor_graph/factor_graph.py File Reference

Classes

- class factor_graph.factor_graph.FactorGraphData

Namespaces

- factor_graph.factor_graph

6.3 /home/alan/PyFactorGraph/factor_graph/measurements.py File Reference

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- class factor_graph.measurements.AmbiguousFGRangeMeasurement
- class factor_graph.measurements.AmbiguousPoseMeasurement
- class factor_graph.measurements.FGRangeMeasurement
- class factor_graph.measurements.PoseMeasurement

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6.4 /home/alan/PyFactorGraph/factor_graph/name_utils.py File Reference

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- factor_graph.name_utils

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- def factor_graph.name_utils.check_is_valid_frame_name
- def factor_graph.name_utils.get_idx_from_frame_name
- def factor_graph.name_utils.get_robot_char_from_frame_name
- def factor_graph.name_utils.get_robot_char_from_number

6.5 /home/alan/PyFactorGraph/factor_graph/parse_factor_graph.py File Reference

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- factor_graph.parse_factor_graph

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- def factor_graph.parse_factor_graph.parse_efg_file
- def factor_graph.parse_factor_graph.parse_pickle_file

6.6 /home/alan/PyFactorGraph/factor_graph/priors.py File Reference

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- class factor_graph.priors.LandmarkPrior
- class factor_graph.priors.PosePrior

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6.7 /home/alan/PyFactorGraph/factor_graph/variables.py File Reference

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