

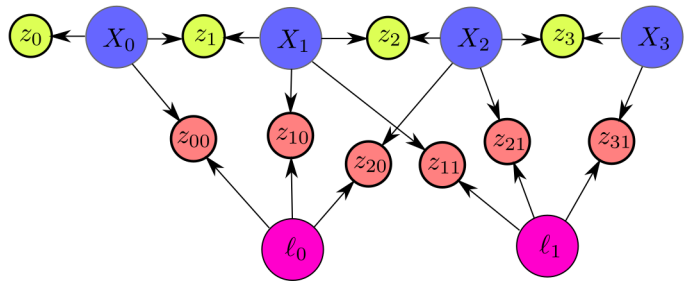


(a)

 Odometry factor  $\exp(\|z_t - h_t(X_{t-1}, X_t)\|_{\Sigma_t}^2)$   
 Landmark factor  $\exp(\|z_n - h_n(X_{\alpha_n}, \ell_{\beta_n})\|_{\Sigma_n}^2)$



(b)