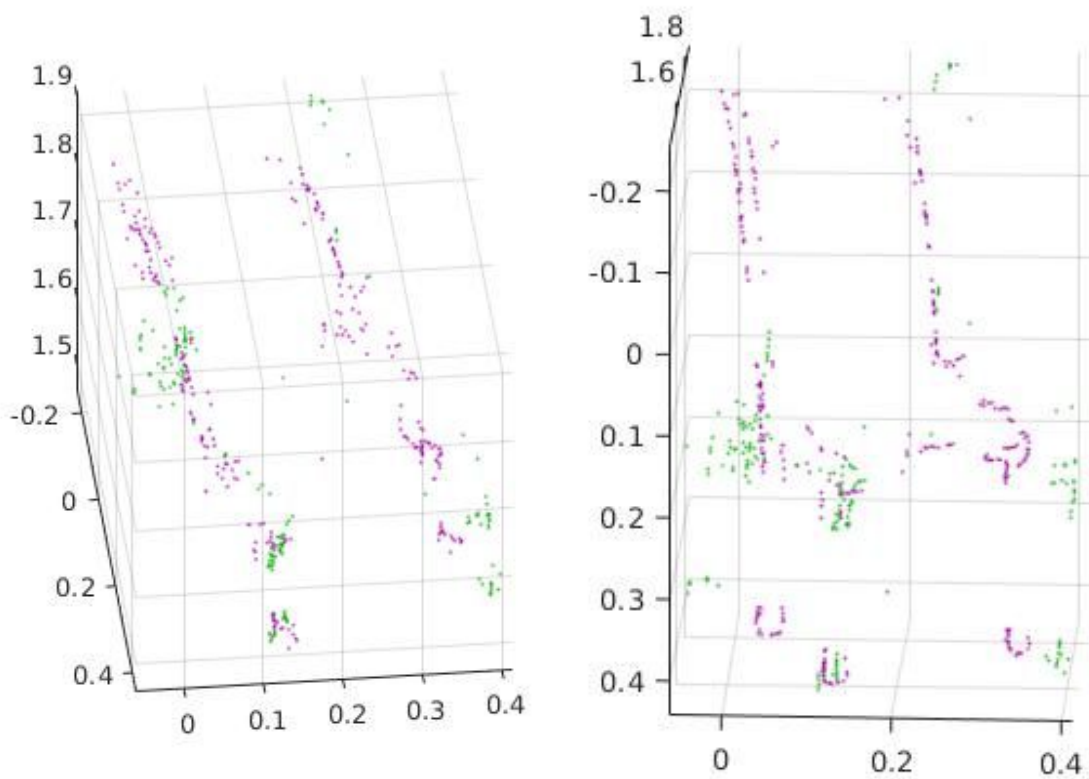


# Relocalization using Objects

Following are the results of relocalization using objects for sparse ICP along with edge SLAM:

The point cloud location initialised by using pose from single view pose shape adjustment.

Point cloud matching:



Trajectory after trying relocalization compared with the ground truth:

