VO Methods, datasets & detalls.						
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Method	Datasets used	Chanacteristic	Defenences			
1 VOLDOR	TUM RGB-D,	Uffizes externally estimated optical	JAC .			
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		probablistic model with generalised				
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		of camera motion, pixel depth & motion	Same			
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		as a video understanding tax.	Sensons 2023			
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9-		unchitecture with some				
4	3	" Mechanic				
		pearlines toom are.				
	8	consider motions in an				
		end to end manner.				
'(4) Pseudo	KITTI	Converts depth maps				
Lidan for		generated steres images into 3D	gea.vix Dag			
Vo		co-condinates point clouds (pseudo	Papers with			
		LIDAR) Utilizera porojection aucore.	code los			
		denx adometry populare to fully explose	the point do			

Dataset: Chanadoustic 1 M ethod soferences Combines a Convolutional Neural Unspeafied Attention based Metwork (CNH) for image feature Deep - Learning ARXIV.OZ Anchitectione ton 3/02 extraction with a long short - Torm Holoenjan 19 Memory (LSTM) network anda much - head attention module for vadeo sequence modeling. Dosigned. bound - grand for neal-time monocular visual odometry, particularly in GRSodem etry for free drone navigation. NONXEN CARRERO tracking @ Mukmokon Oxford Markoning Eskmales the full SE (3) Moval Odometry Datased (and) trajectory of every motion in welkitten & withe scene, including seman Roboño . she the egomotion, without onelying on esp appearance based information. nyport brown Extends tradictional visual - deplaced adonetry pipelines with multipotion sign mondre of nother regini en and tracking techniques of an Coxos Boos Depth & flow for & VO COF-vo) @ DF-40 algorithm evaluated for ARXIV. OSY Robocar, stabultaen in souny weather 4 seasons, conditions. Portains well for Internal Short - nange distances (Loom) Sew derbars6 in Unban Daliving Scenarios under Dataset. (e) Deep Parts Uhlizes a moved snecwhent Visual Octometry NewsIPS network anchitecture designed for unspeatied tracking image patches across 2023 time.

1	Method.	Downer	Chanaderistics	References
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		har waster	a small set of edges to improve	· 2623
		a della congression of the	Computational efficiency without.	
		O gallehan	Sacrificing accuracy.	
	0	Synthetic &	Integrates learning - based	
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	-	datasets	low-latercy camera tracking	2023
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	VO in Under	word a life of the second	learning - based monocular	
	Tenan	6.000 800009	VO in underwater environment	

Tracking Thread processing of incoming frames to estimate the corneral pose a manage keytarames. Here's a breakdown of the tracking thread : Implementation, * Extract ORB features * System Initialization. * for commation * Local Map Tracking. * Keyframe deasion. EMM OF : HOLD * Relocalization System Components of ORB SLAM 3. TRACKING EXTRACT INITIAL POSE FRAME MEW TRACK ORB ESTIMATION FROM KEYFRAME LOCAL LAST FRAME , RELOCALIZA DECISION MAP UMI JION OR MAP CREATION INTEGRATION Key Frame Local Mapping Loop Correction Keykrame Place seesgnition fuel BA Presention Obhalls Loop Recent map Posits fired BA/ essential fuston compute Ercibi Database query < SYM3/BE3 Nap Newpoints creation weldeng ophmize spolate Wende

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