Cloud assembly	drl::CircularBuffer	drl::LaserAssembler
<b>+</b>	a nelu Aprovimato Vovol Crid	• noto Dadius Outlier Damous
Filtering	pcl::AproximateVoxelGrid pcl::CovarianceSampling pcl::CropBox	pcl::RadiusOutlierRemoval pcl::RandomSample pcl::StatisticalOutlierRemoval
<b> </b>	pcl::PassThrough	• pcl::VoxelGrid
Normal estimation	drl::NormalEstimatorSAC pcl::MovingLeastSquares	pcl::NormalEstimationOMP pcl::PrincipalCurvaturesEstimation
<b>+</b>		)
Keypoint detection	pcl::ISSKeypoint3D	• pcl::SIFTKeypoint
Keypoint description	pcl::ESFEstimation pcl::FPFHEstimationOMP pcl::PFHEstimation	pcl::ShapeContext3DEstimation pcl::SHOTEstimationOMP pcl::UniqueShapeContext
RANSAC initial pose estimation	drl::SAC-IA-OMP pcl::SAC-IA	
	pcl::GeneralizedICP	and JCDW/HhMarrada
Point cloud registration	pcl::GeneralizedicP pcl::ICP pcl::ICP2D	<ul><li>pcl::ICPWithNormals</li><li>pcl::NDT</li><li>pcl::NDT2D</li></ul>
-	pcl::ICPNonLinear	J
Registration analysis	Inliers   outliers RMSE % inliers   % outliers % inliers   % outliers angular	Maximum allowed pose corrections (translation   rotation)
	distribution	)
Map update	drl::MapIntegration	• OctoMap