Cloud assembly
- drl::CircularBuffer
- drl::LaserAssembler

Filtering
- pcl::AproximateVoxelGrid
- pcl::CovarianceSampling
- pcl::CropBox
- pcl::PassThrough
- pcl::RadiusOutlierRemoval
- pcl::RandomSample
- pcl::StatisticalOutlierRemoval
- pcl::VoxelGrid

Normal estimation
- drl::NormalEstimatorSAC
- pcl::MovingLeastSquares
- pcl::NormalEstimationOMP
- pcl::PrincipalCurvaturesEstimation

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

Point cloud registration
- pcl::GeneralizedICP
- pcl::ICP
- pcl::ICP2D
- pcl::ICPNonLinear
- pcl::ICPWithNormals
- pcl::NDT
- pcl::NDT2D

Registration analysis
- Inliers | outliers RMSE
- % inliers | % outliers
- % inliers | % outliers angular distribution
- Maximum allowed pose corrections (translation | rotation)

Map update
- drl::MapIntegration
- OctoMap