

PoseGraph2D的函数分类

构造函数

AddTrimmer

数据输入

AddImuData

AddOdometryData

AddFixedFramePoseData

AddLandmarkData

AddNode

GetLocalToGlobalTransform

AppendNode

AddTrajectoryIfNeeded

CanAddWorkItemModifying

AddWorkItem

主要流程函数

DrainWorkQueue

ComputeConstraintsForNode

InitializeGlobalSubmapPoses

ComputeLocalToGlobalTransform

GetInterpolatedGlobalTrajectoryPose

ComputeConstraint

GetLatestNodeTime

RunOptimization

HandleWorkQueue

UpdateTrajectoryConnectivity

DeleteTrajectoriesIfNeeded

析构函数

WaitForAllComputations

其他接口

获取数据

GetTrajectoryNodes

获取节点信息

GetTrajectoryNodePoses

constraints

获取约束

GetLocalToGlobalTransform

获取local坐标系到global标系的坐标变换

GetAllSubmapPoses

GetSubmapData

获取地图

GetAllSubmapData

GetSubmapDataUnderLock

GetTrajectoryData

GetLandmarkPoses

GetImuData

获取传感器数据

GetOdometryData

GetFixedFramePoseData

GetLandmarkNodes

GetConnectedTrajectories

获取轨迹信息

GetTrajectoryStates

从pbstream文件中生成位姿图

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RunFinalOptimization

IsTrajectoryFinished

FinishTrajectory

DeleteTrajectory

SetInitialTrajectoryPose

SetGlobalSlamOptimizationCallback