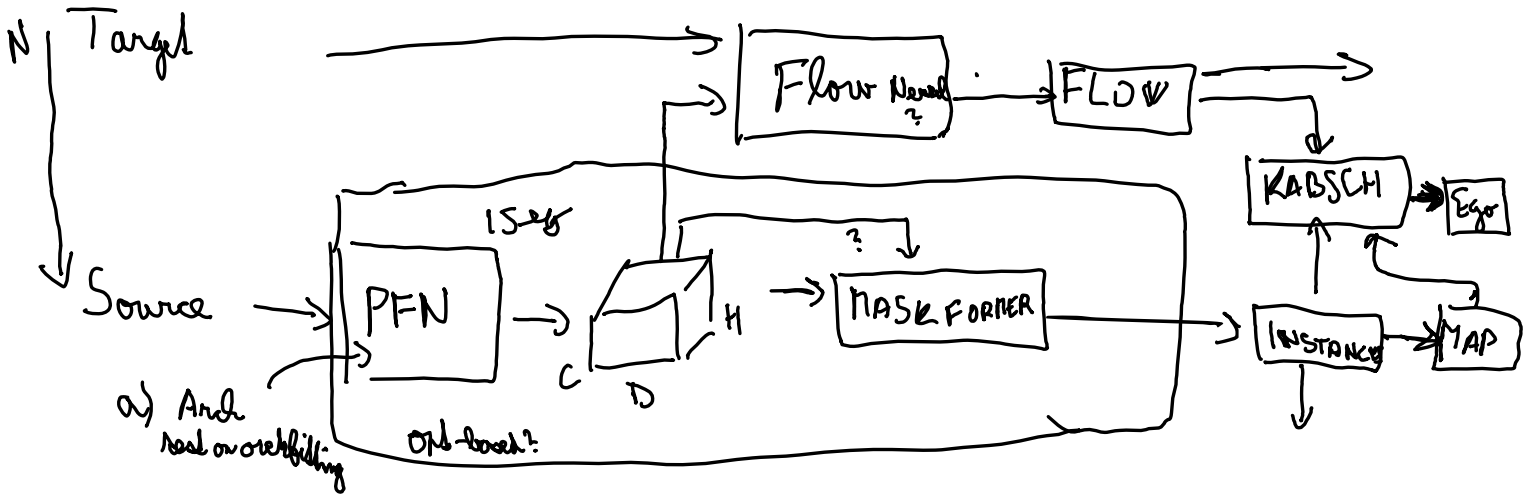

KITTI - ICP

(fr, down)

Meos

$$\mathcal{L}^{odo} = \mathcal{L}_{rigid\,chpk} + \mathcal{L}_{velocity} + \mathcal{L}_{NN\,ego} \checkmark$$

$$\mathcal{L}^{flow} = \mathcal{L}_{prior} + \mathcal{L}_{NN} + \mathcal{L}_{csm} + \mathcal{L}_{rigid} + \mathcal{L}_{Ego} + \mathcal{L}_{velocity} + \mathcal{L}_{Freespace}^{\mathcal{L}_{ATS}\,?}$$

$$\mathcal{L}^{IS} = \mathcal{L}_{rigid} + \mathcal{L}_{csm} + \mathcal{L}_{geo\,inv?} + \mathcal{L}_{Ego} + \mathcal{L}_{velocity} + \mathcal{L}_{Freespace} \;!$$

1) Temp sequence
2) joint SF, IS, Ego
3) real-time, large-scale
4) Visibility in SF, IS?

Ruslan - odo, codes, MAP.

$$\boxed{\mathcal{L} = \mathcal{L}^{odo} + \mathcal{L}^{flow} + \mathcal{L}^{IS}} + \mathcal{L}_{ground?} + \text{"}\mathcal{L}_{art\,label}\text{"} \approx \mathcal{L}_{Ego}$$

(background)