Table 1: List of SLAM / VO algorithms

Name	Refs	Code	Sensors	Notes
AprilSLAM	[**Wang2016**] (2016) [**Olson2011**] (2011)	Link	Monocular	Uses 2D planar markers
ARM SLAM	[**Klingensmith2016**] (2016)	-	RGB-D	Estimation of robot joint angles
BundleFusion	[**Dai2017**] (2011)	Link	RGB-D	Focus on 3D-scanning
CD SLAM	[**Pirker2011**] (2011) [**Pirker2010**] (2010)	-	Monocular	Focus on dynamic environments Custom descriptor
C-KLAM	[**Nerurkar2014**] (2014)	-	Monocular, IMU	Usage of inter-keyframe information
CNN SLAM	[**Tateno2017**] (2017)	-	Monocular	Depth prediction via CNN
COP SLAM	[**Dubbelman2015**] (2015) [**Dubbelman2013**] (2013) [**Dubbelman2010**] (2010)	-	- (back-end)	Sparse pose-graph Scale drift aware (Lie groups)
CoSLAM	[**Zou2013**] (2013)	Link	Multiple cameras	Dynamic environments
DPPTAM	[**Concha2015b**] (2015)	Link	Monocular	Dense, estimates planar areas
DSO	[**Engel2016**] (2016)	Link	Monocular	Semi-dense odometry Estimates camera parameters
DT SLAM	[**Daniel2014**] (2014)	Link	Monocular	Tracks 2D and 3D features (indirect) Creates combinable submaps Can track pure rotation
DTAM	[**Newcombe2011**] (2011)	Link	Monocular	Dense, GPU reliant Robust to rapid motion
DVO	[**Kerl2013**] (2013)	Link	RGB-D	Entropy based method for loops
FrameSLAM	[**Konolige2008**] (2008)	-	Stereo	CenSure features
GDVO	[**Zhu2017**] (2017)	Link	Stereo	Dense Dual Jacobian scheme
GPSLAM	[**Pirker2011a**] (2011)	-	RGB-D	Sparse map, dense occupancy grid
GP-SLAM	[**Yan2017**] (2017) [**Dong2017**] (2017)	Link		Sparse gaussian process regression for Lie groups

KinectFusion	[**Pirovano2012**] (2012) [**Izadi2011**] (2011) [**Newcombe2011a**] (2011)	Link	RGB-D	Object segmentation Uses only depth sensor GPU reliant
Kintinious	[**Whelan2013a**] (2013) [**Whelan2013**] (2013) [**Whelan2012**] (2012)	Link	RGB-D	Extension of KinectFusion
LSD SLAM	[**Engel2015**] (2015) [**Engel2014**] (2014) [**Engel2013**] (2013)	Link	Monocular, Stereo	Semi-dense Runs on CPU
MonoSLAM	[**Russo2014**] (2014) [**Davison2007**] (2007)	Link	Monocular	Particle filter back-end
NID SLAM	[**Pascoe2017**] (2017)	-	Monocular	Robust to lighting and weather GPU reliant
OKVIS	[**Leutenegger2015**] (2015) [**Leutenegger2014**] (2014) [**Leutenegger2013**] (2013)	Link	Stereo IMU	Focus on IMU integration
ORB SLAM	[**Mur-Artal2017**] (2017) [**Mur-Artal2016a**] (2016) [**Mur-Artal2015**] (2015) [**Mur-Artal2014**] (2014)	Link	Monocular, Stereo (v2), RGB-D (v2)	ORB descriptor Runs on CPU Extension of PTAM
Pop-up SLAM	[**Yang2016**] (2016)	Link	Monocular	CNN predicts planar surfaces
PTAM	[**Klein2007**] (2007)	Link	Monocular	Parallel tracking and mapping
RD SLAM	[**Tan2013a**] (2013)	-	Monocular	Focus on dynamic environments
REBVO	[**Tarrio2016**] (2016)	Link	Monocular, IMU	Odometry on edges
REMODE	[**Pizzoli2014**] (2014)	Link	Monocular	Dense GPU reliant
RGB-D SLAM	[**Endres2012**] (2012) [**Endres2012a**] (2012)	Link	RGB-D	
RKSLAM	[**Liu2016**] (2016)	Link	Monocular, IMU	Robust to fast motion and rotation
ROCC	[**Buczko2017**] (2017) [**Buczko2016**] (2016) [**Buczko2016a**] (2016)	-	Monocular, Stereo	Decouples rotation and translation Feature outlier removal Focus on automotive

ROVIO	[**Bloesch2015**] (2014)	Link	Monocular, IMU	Focus on IMU integration Relative representation
RSLAM	[**Mei2011**] (2011)	-	Stereo	Relative representation No global optimization
ScaViSLAM	[**Strasdat2011**] (2011)	Link	Stereo	Scale drift aware through using Lie groups
SLAM++	[**Milford2012**] (2012) [**Salas-moreno2013**] (2013)	-	RGB-D	Uses KinectFusion Real-time object recognition
SlamDunk	[**Fioraio2015**] (2015)	Link	RGB-D	Runs on CPU
SOFT	[**Cvisic2015**] (2015)	-	Stereo, IMU	Odometry based on feature selection Separates rotation and translation
S-PTAM	[**Pire2017**] (2017) [**Pire2015**] (2015)	Link	Stereo	Robust to lighting changes feature-based, BRISK descriptor
SVO	[**Forster2017**] (2017) [**Forster2014a**] (2014)	Link	Monocular	Focus on runtime (embedded devices) Needs a high framerate
V-LOAM	[**Zhang2015**] (2015)	-	Monocular, LIDAR	Combination of camera and LIDAR