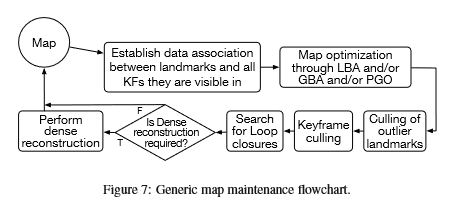
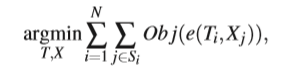
optimizes the map using either Bundle Adjustment or Pose Graph Optimization.

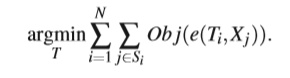


* New 3D landmarks are triangulated based on camera pose estimates.
* Map maintenance establishes data association between keyframes in the map one of two ways:
  + Global Bundle Adjustment (GBA) using the entire set of keyframes in the map
  + Local Bundle Adjustment (LBA, also known as windowed optimization) using a subset of keyframes in the map
* Outlier landmarks flagged during optimization are culled (removed).
* Redundant keyframes are also culled to boost performance.

**Bundle Adjustment:**

Cost function: where Ti is a keyframe pose estimate, N is the number of keyframes in the map or in the subset of the map, Si Is the set of 3D landmarks observed in keyframe I, and e(Ti,Xj) is the reprojection error of a landmark Xj on a keyframe Ti.

**Pose Graph Optimization:**

Cost function: This explicitly distributes the accumulated drift along the entire map.