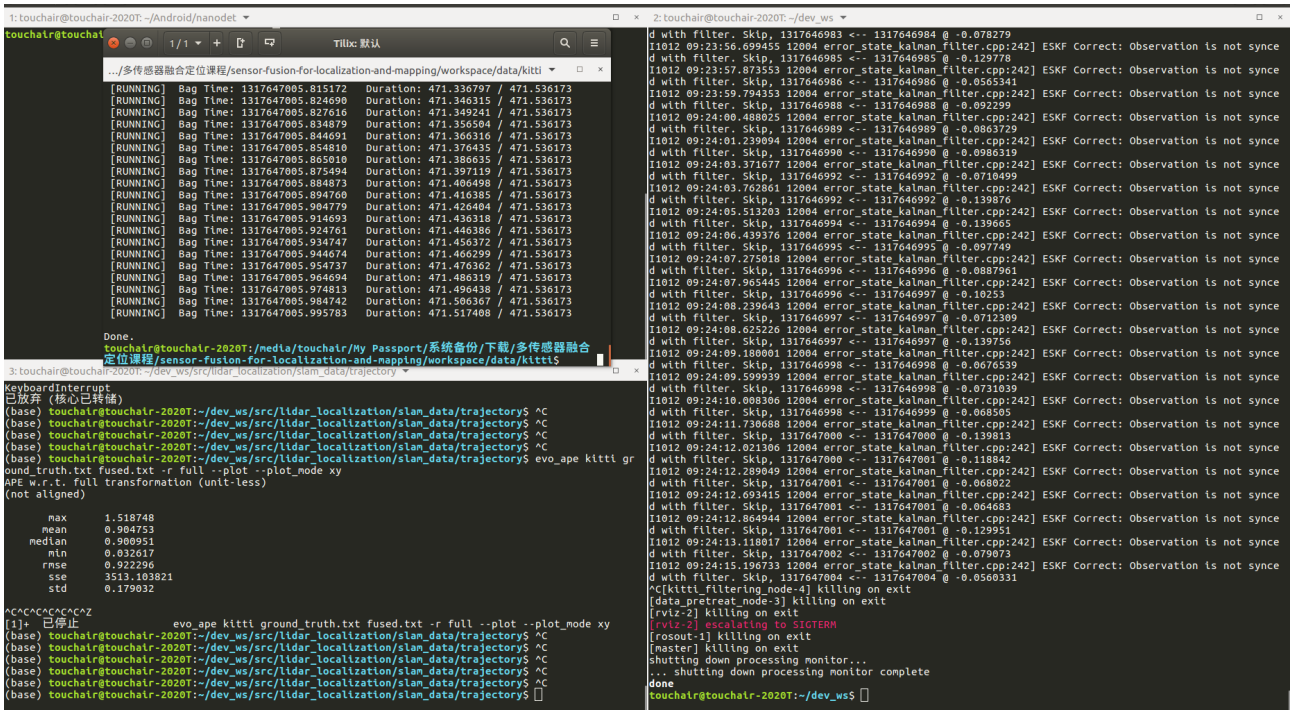
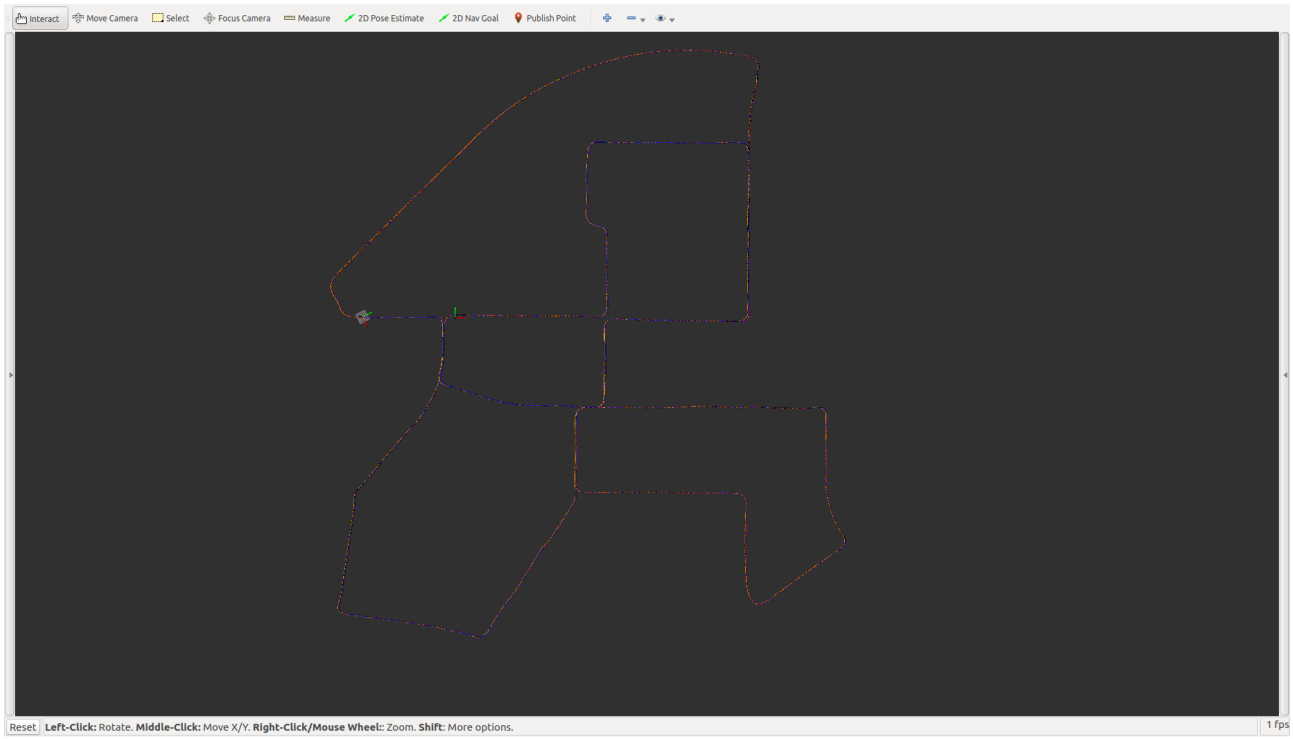
1、跑通滤波程序，截图如下

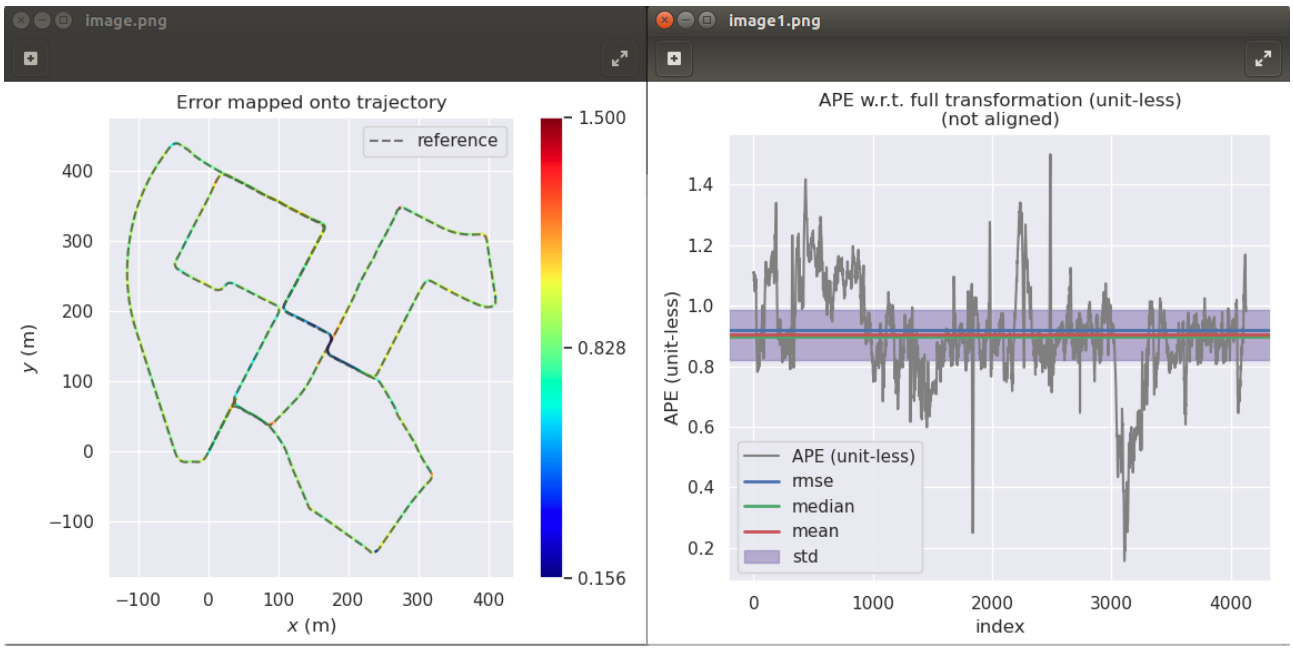




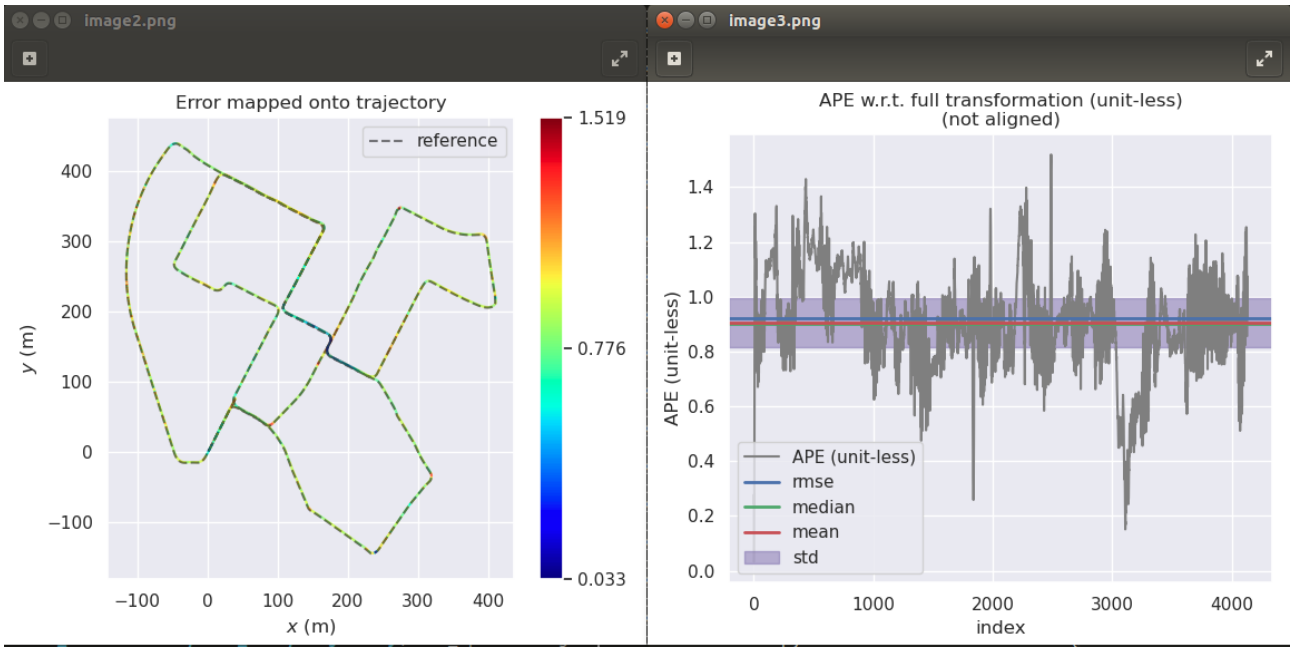
2、evo 评估

考虑误差的随机游走

a、laser

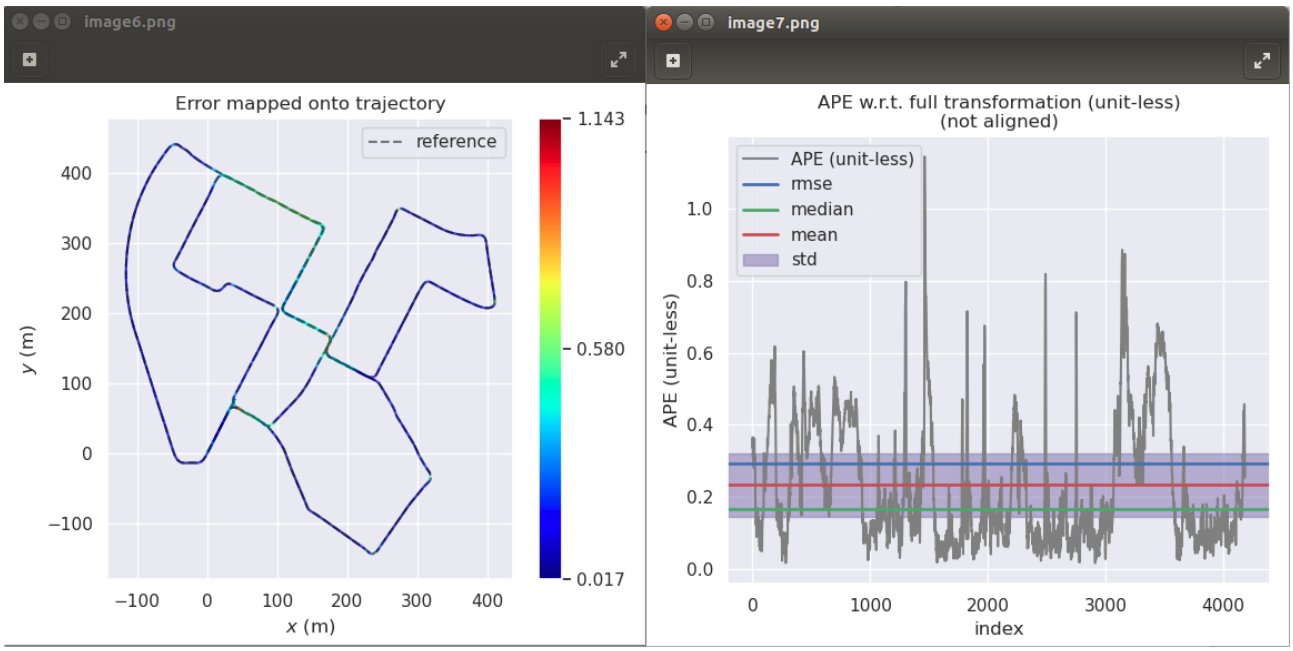


b、fused

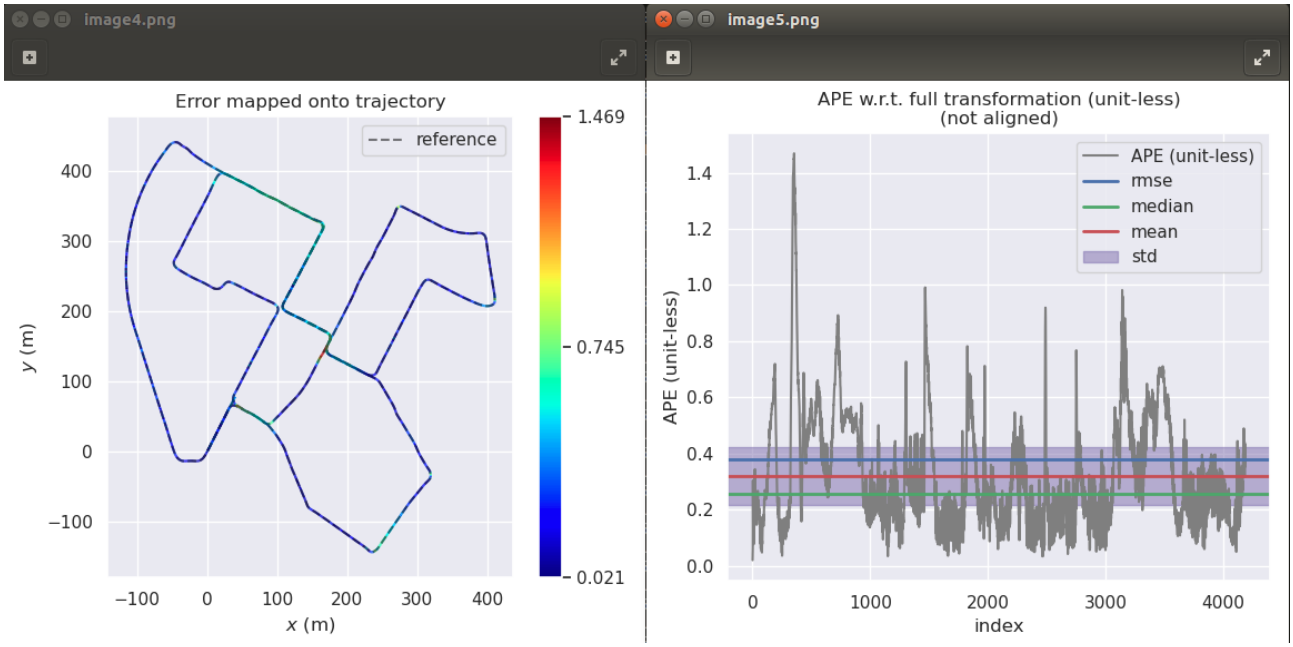


不考虑误差的随机游走

a、laser

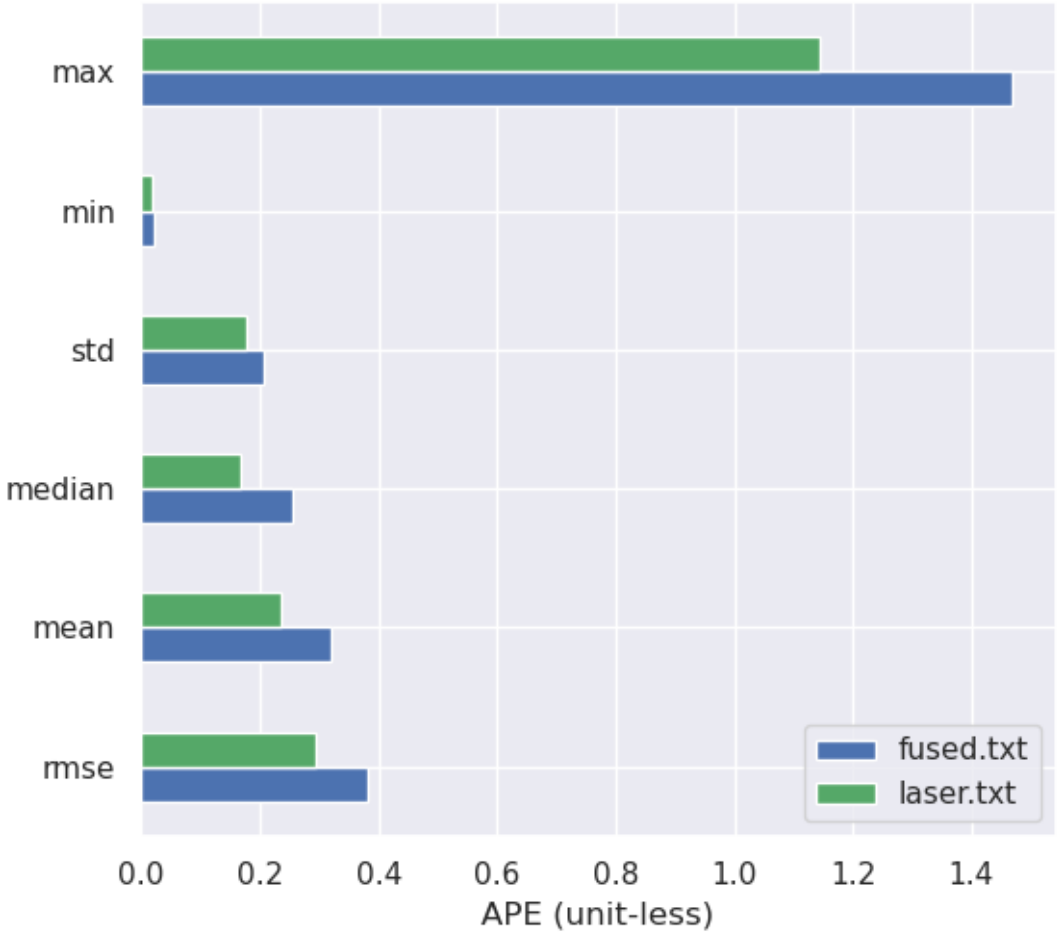


b、fused

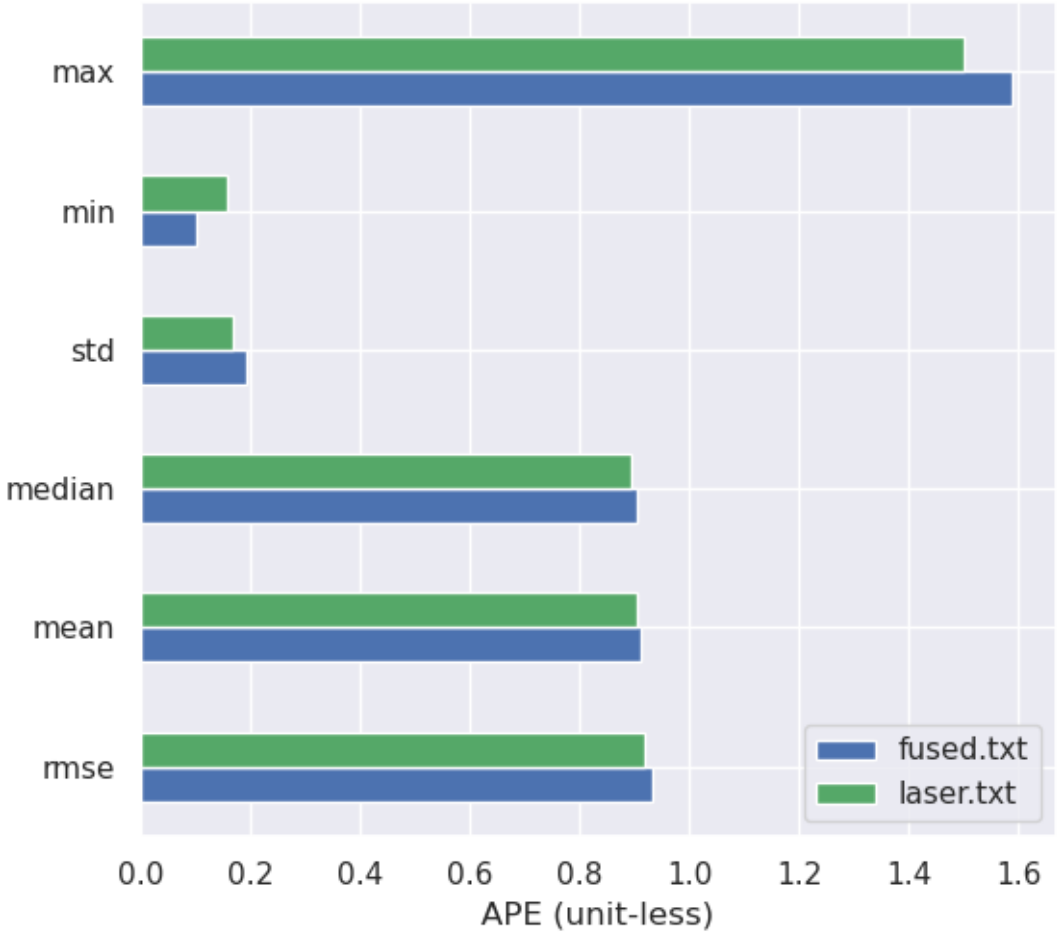


3、不同噪声设置情况下的结果对比

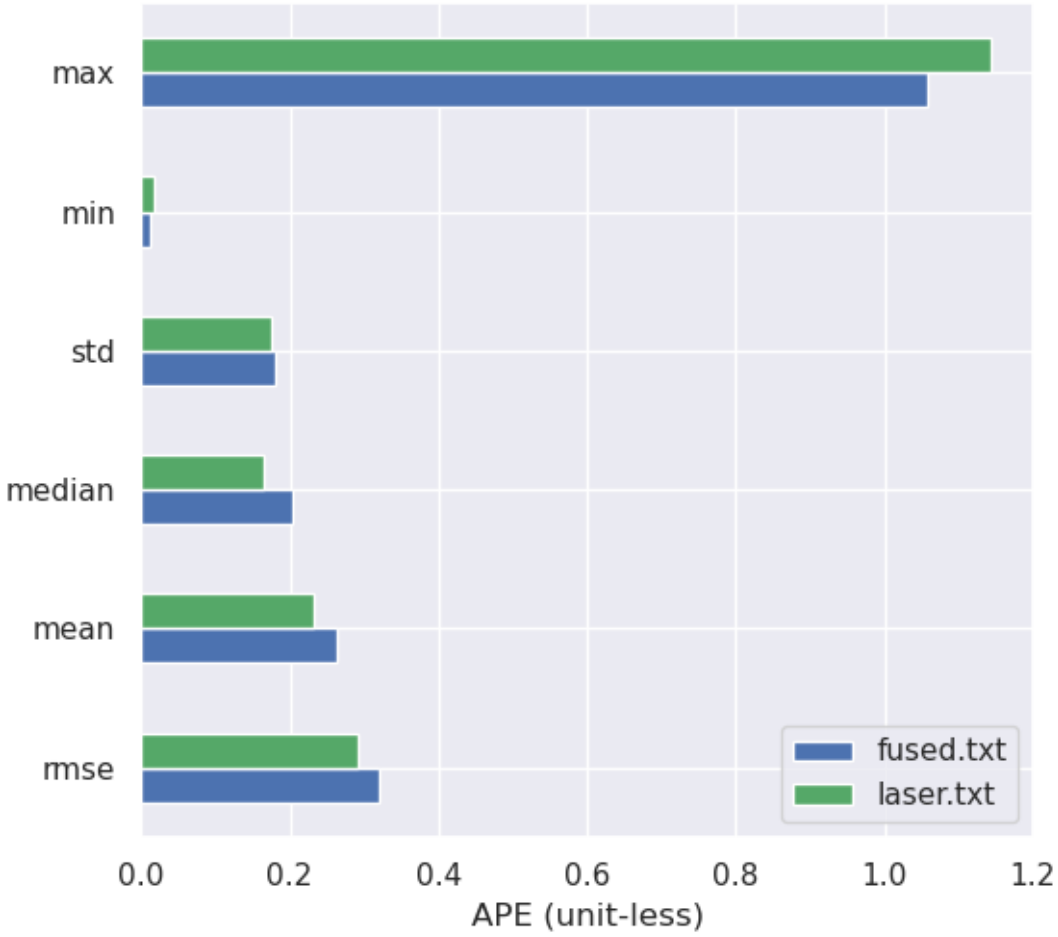
```
process:
    gyro: 1.0e-4
    accel: 2.5e-3
    bias_accel: 2.5e-3
    bias_gyro: 1.0e-4
    bias_flag: false
measurement:
    pose:
        pos: 1.0e-4
        ori: 1.0e-4
    pos: 1.0e-4
    vel: 2.5e-3
```




```yaml
process:
    gyro: 1.0e-3
    accel: 2.5e-2
    bias_accel: 2.5e-2
    bias_gyro: 1.0e-3
    bias_flag: false
measurement:
    pose:
        pos: 1.0e-5
        ori: 1.0e-5
    pos: 1.0e-4
    vel: 2.5e-3
```




```yaml
process:
    gyro: 1.0e-2
    accel: 2.5e-1
    bias_accel: 2.5e-1
    bias_gyro: 1.0e-2
    bias_flag: false
measurement:
    pose:
        pos: 1.0e-6
        ori: 1.0e-6
    pos: 1.0e-5
    vel: 2.5e-4
```


max
min
std
median
mean
rmse
fused.txt
laser.txt
0.0
0.2
0.4
0.6
0.8
1.0
1.2
APE (unit-less)