

1 Experimental Results on Intel L515

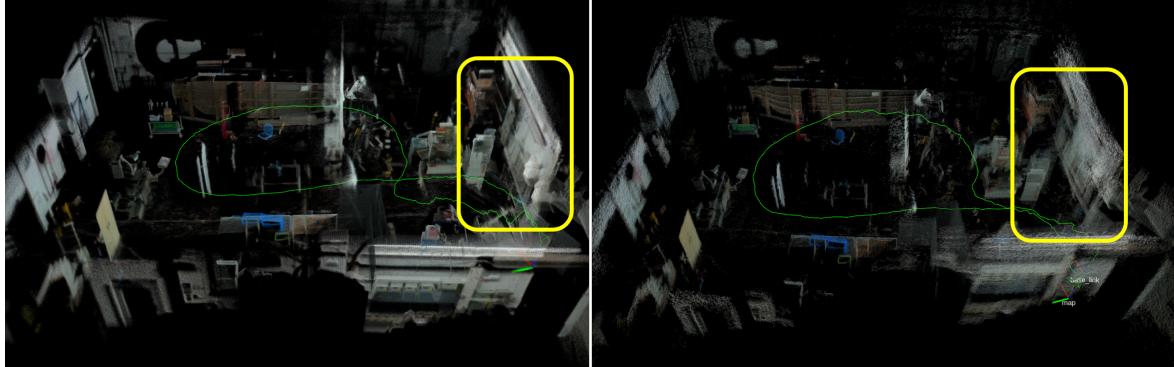


Figure 1: The mapping result of our method (left) and SSL-SLAM (right). The point cloud color information is provided by L515.

2 Experimental Results on Livox Avia

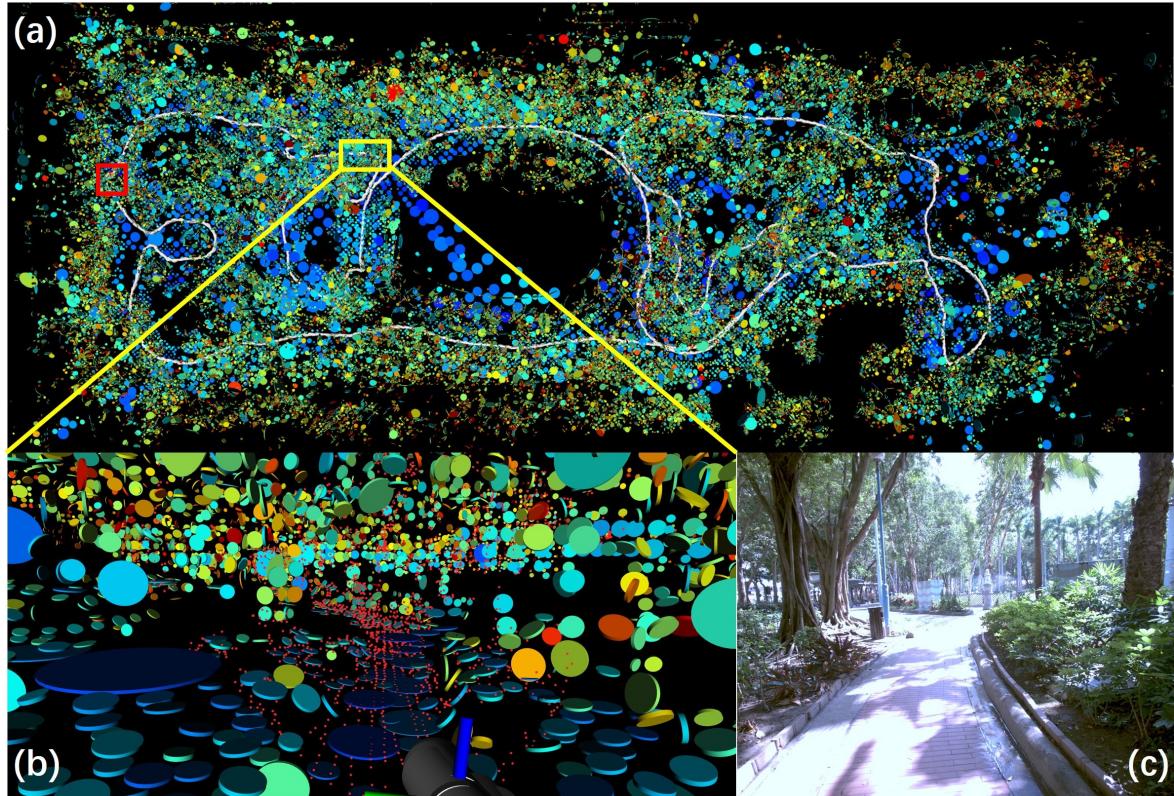


Figure 2: (a) The plane map constructed by our algorithm in park environment. The red rectangle records the starting and ending point. The golden rectangle indicates the position of a case frame. (b) and (c) are the LiDAR data and camera data corresponding to the case frame.

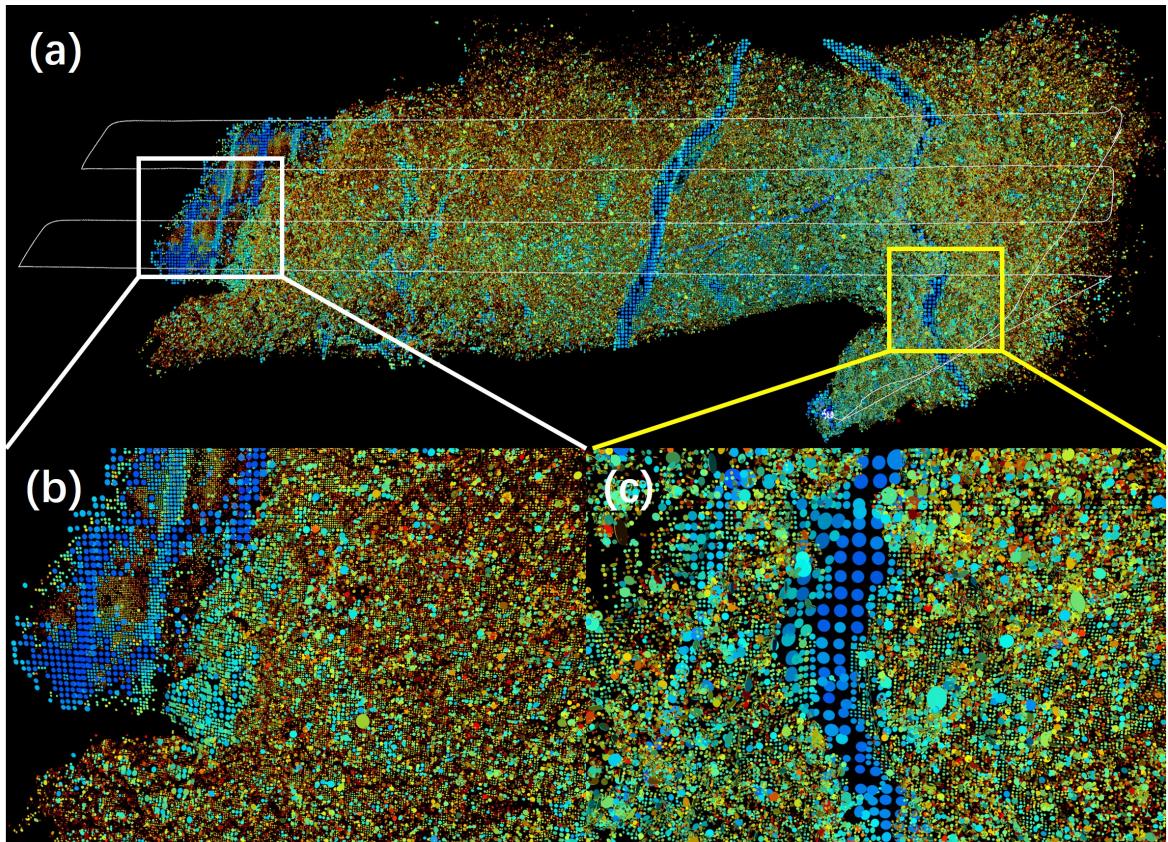


Figure 3: (a) The mapping results of a mountain. (b) and (c) show the partially enlarged view of plane map.