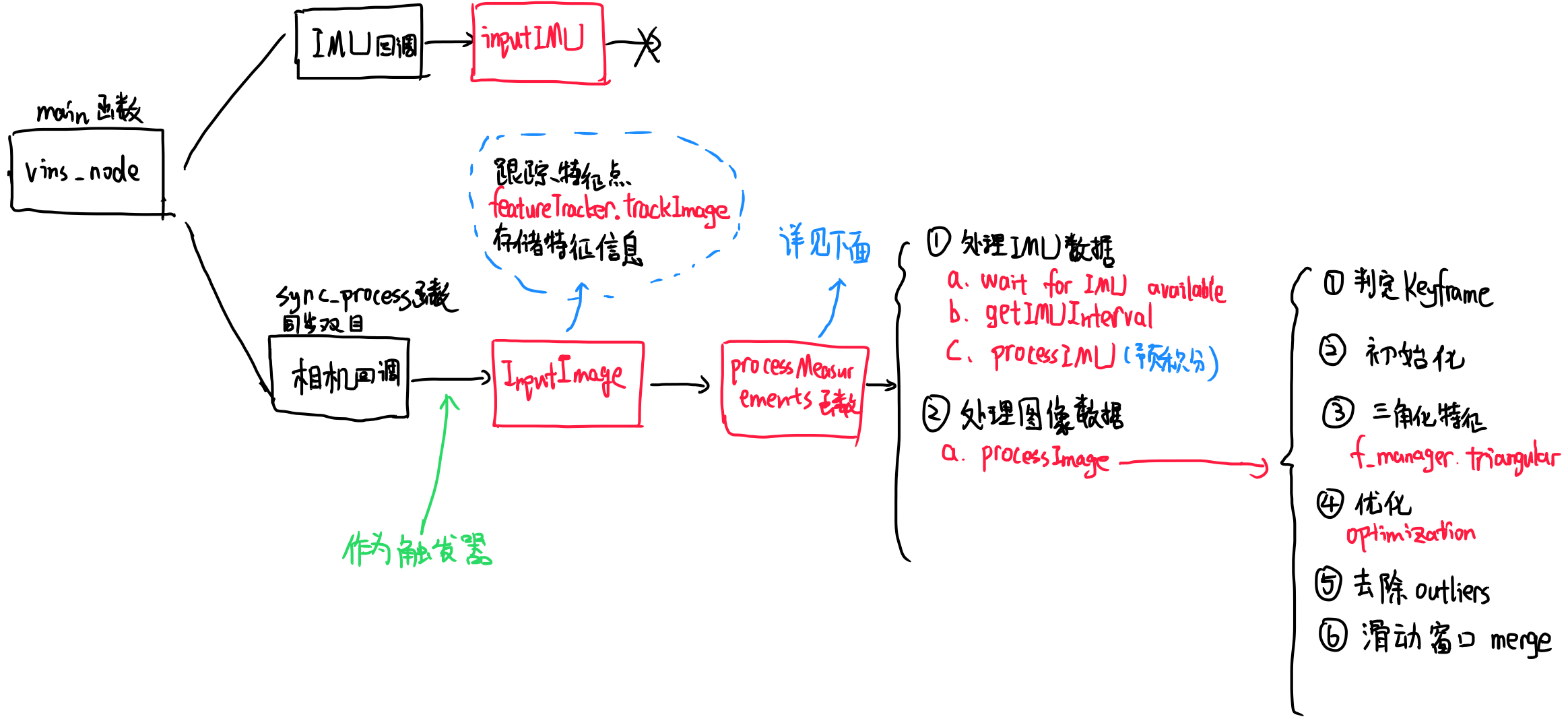
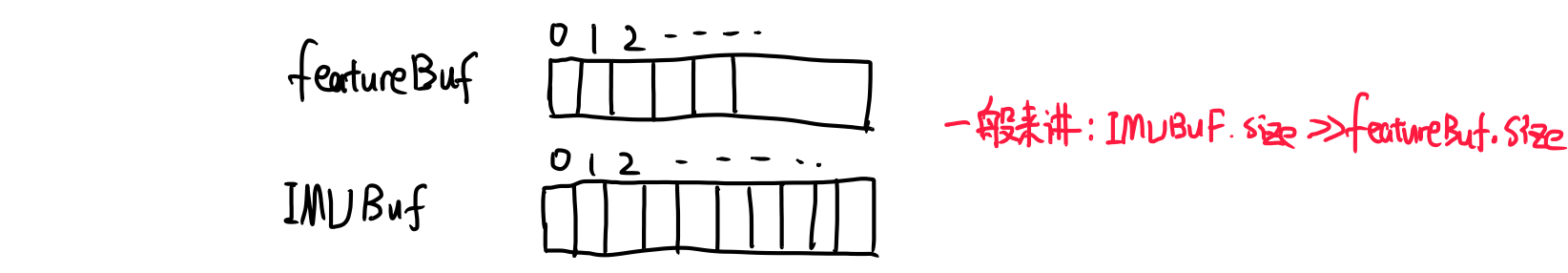


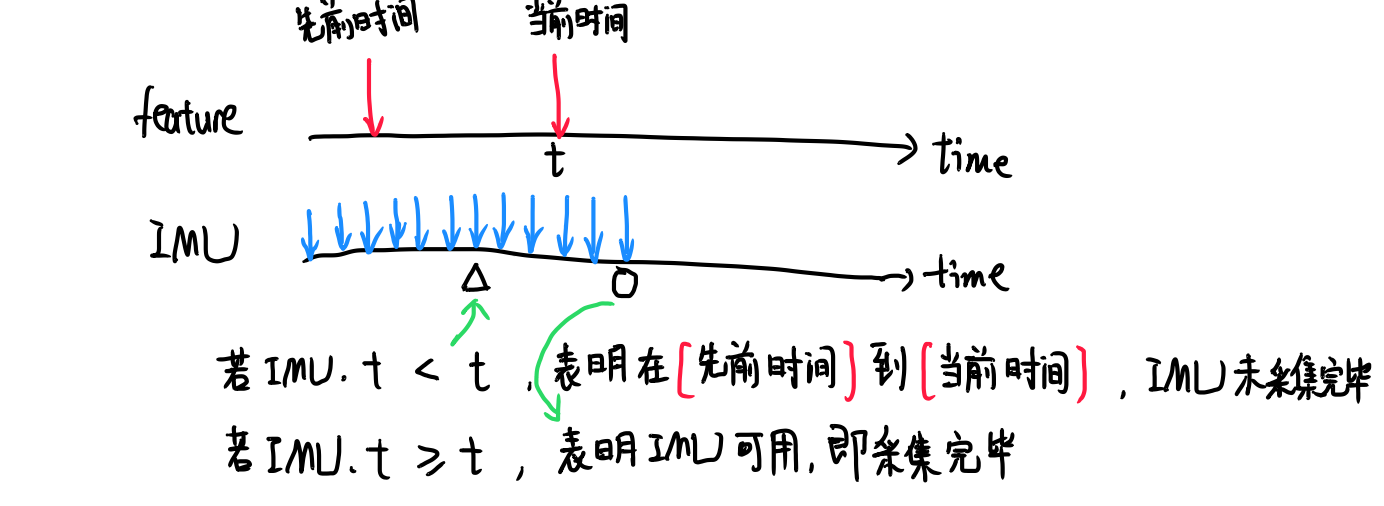
§ VINS 流程



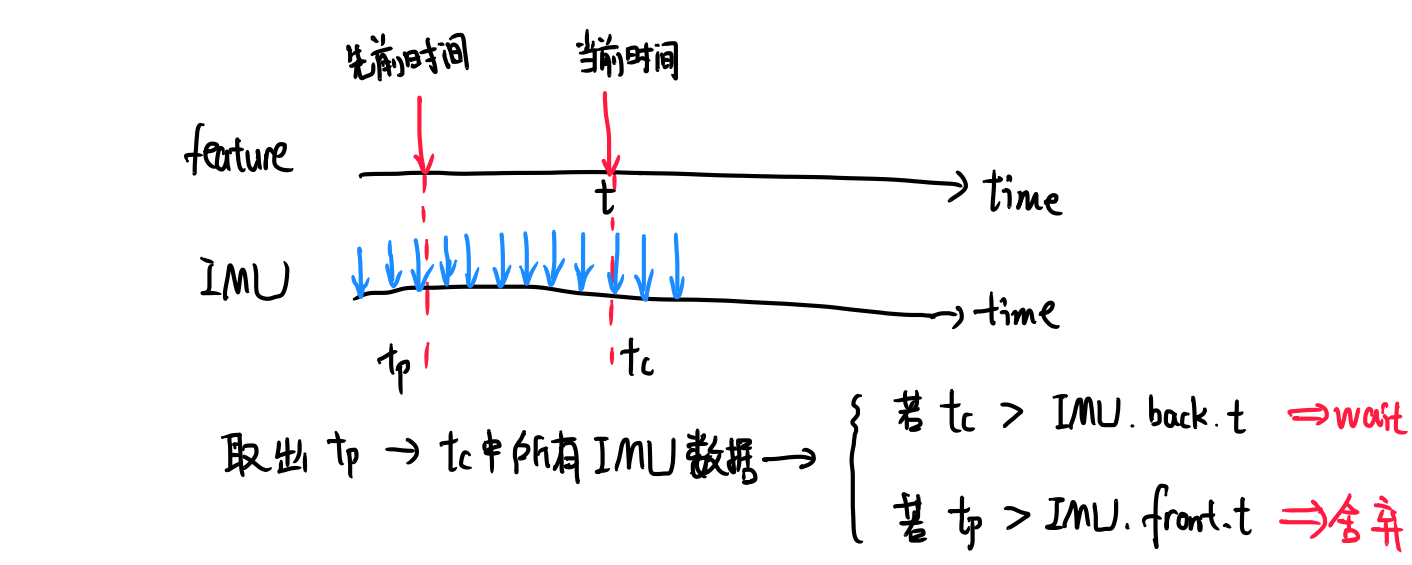
§ processMeasurements 函数



Step 1: 判断IMU是否可用:
若 `featureBuf` 非空, 则取出一个, 然后等待IMU



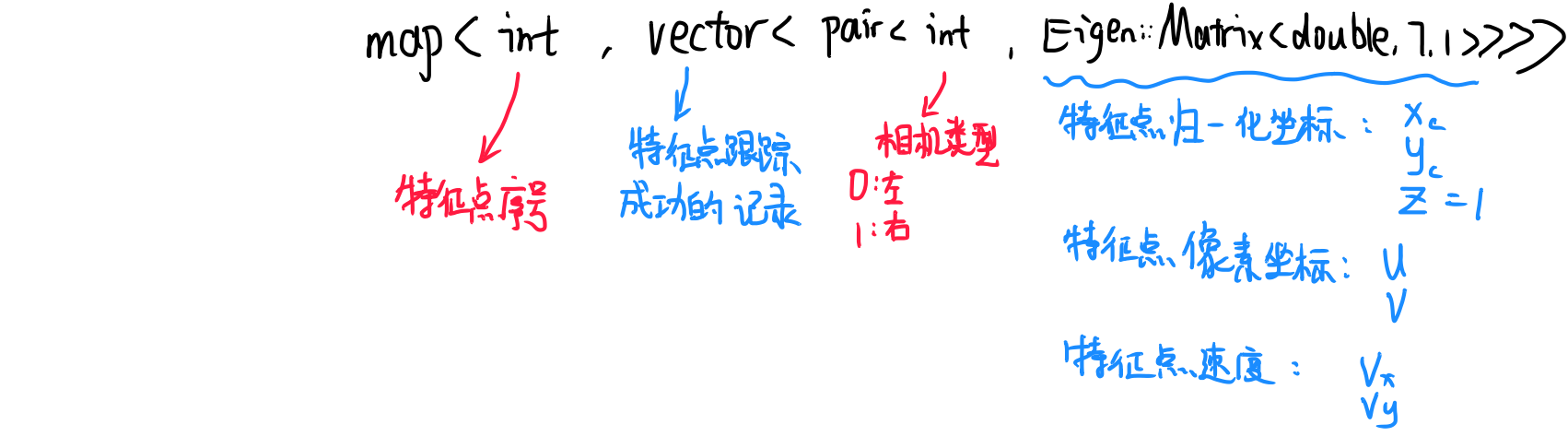
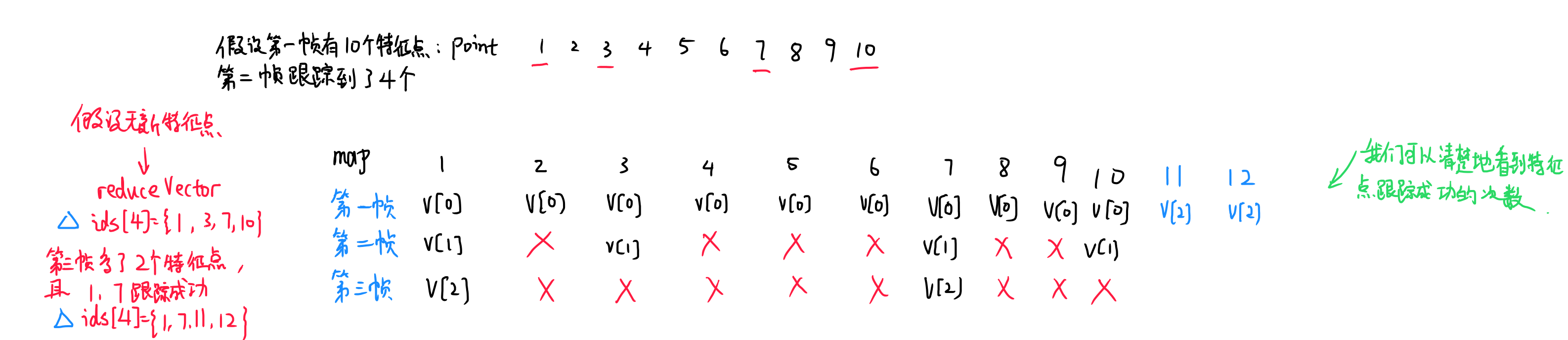
Step 2: getIMUInterval



Step 3: IMU 预积分

`pre-integration.push-back` 函数: 计算预积分并压入队列
a. `propagate`
b. `midPointIntegration`

§ trackImage 特征点提取+跟踪流程



§ 图像处理

- ① 判断关键帧
`f_manager.addFeatureCheckParallax` 函数 判断关键帧
- ② 初始化
- ③ 三角化特征
`f_manager.triangular` 函数
- ④ 优化
`optimization` 函数
- ⑤ 除去外点, outliers
- ⑥ 滑动窗口 merge