Laser odometry

- Using scans from the scans.npy file, reconstruct robot trajectory using frame-to-frame and keyframe approaches
- Compare results with ground-truth data from poses.npy
- Fine-tune ICP and keyframe parameters to achieve better precision
- Build occupancy grid map using trajectory acquired with keyframe approach

Keyframe approach

- Remember initial pose and scan as a keyframe
- For each scan:
  - Perform dx = ICP(scan, keyframe_scan) and remember the resulting pose (keyframe_pos + dx) as a position for given scan
  - If dx is bigger than the given threshold, set current scan and position as a new keyframe