LiDAR

Dynamic weight linear systems

Calculate the kernel weights | *Construct the Jacobian matrix* | *Building linear systems*

Adaptive error threshold

Calculate velocity and acceleration

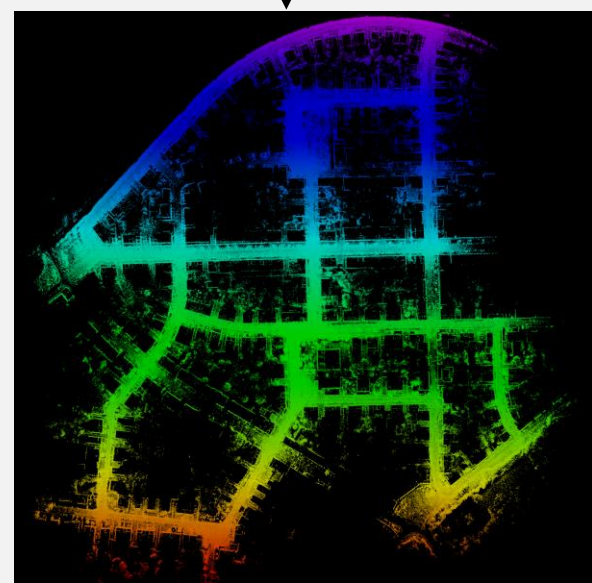**Local maps of voxels**

Voxel mapping and coordinate calculation

FIFO update

Pose transformation and management

Adaptive ICP registration

Initialize pose | *Iterate update pose* | *Judgment convergence*

Calculating motion differences

Dynamic weight adjustment

Adaptive motion prediction

Collect historical poses | *Weighted historical poses* | *Predict next pose*

Update adaptive threshold

Global map