Since last time, I tried to improve the results by pre-rotating the data, as you taught me to do.

I'm trying everything with a global REGISTRATION between two points first.

There is something that I found out while running this process.

That is there are so many points that it's hard to know which one is the object.

The Lidar sensor is detecting everything in the room.

So I tried to eliminate the unwanted point clouds.

The figure on the left is a picture from the Lidar sensor

The area circled in red is not necessary, so I eliminated it.

After rotating the object, I decided to set a threshold on the x and y values so that only the object itself and the pillar are affected.

As a result, the point cloud synthesis of 100 and 101 has a better chance of working.

But there's still two problem.

Even though we are running the same code, sometimes we get bad results!

・壁があると助けになる

・壁があるとより大変になる

・最後にはonly object

・linear oq

Converge to

Initial position を与えるとうまく行く

Fitness functionのvalueが違うはず

How

・Preprocessing is 平行移動

・Open3d以外のパッケージ

最後には他のアルゴリズムも比べる

・another method, another proprec

・not pillar, make a box simple box, paper bin

・4点でやりたい

**1/20**

aaaa