

Online large-scale SLAM with stereo visual-inertial sensors

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Our mission



Related work and state of the art

Graph-based SLAM

Sensor setup: the VI-Sensor

First steps



Least squares optimization



Pipeline

Videos

Hand-held dataset: Aula magna

Bike mounted dataset: Streets in San Lorenzo

Results: hand-held

Results: bike mounted

Results: KITTI

Conclusions and remarks

Future work

