

→ Pointcloud buffer (thread safe) ✓ > 20sec { remove }

✓ ⇒ thread safe

→ keyframe.cpp → transability grid. (safe if keyframe is safe) ✓

↳ mastergridmap mutex (from localmap.cpp)

↳ gridmapmutex (to safeguard mastergridmapmutex & pgridmap-)

↳ setsetpose / setpose [Non blocking] ⇒ add pose to queue [Local queue]

↳ recompute cache() [Blocking] ⇒ process the poses.

→ Helpers.cpp ✓

→ Localmap.cpp ✓

↳ keyframeupdatequeue (pushed by system.cpp)  
(processes in a separate thread)

↓ <thread>

Run Update Queue  
(updates kf value (poses)  
from queue  
active: sleep 100ms)

↓ <thread>

Run Transability  
Global updates (all kfs)  
1 kf every 100ms  
500ms sleep after all kfs.

↓

<thread>

Run Local kfs

max local queue size = 10  
process all local kfs  
sleep 1s

→ Parameters.cpp ✓✓

→ System.cpp ✓✓

Add kf

Tsdouble

TsLong

with PCL

without PCL

update kf

Tsdouble

TsLong