

## Method Overview

Our approach is based on FAST-LIVO2 (Fast LiDAR-Inertial-Visual Odometry) with integrated Pose Graph Optimization (PGO). The system combines LiDAR, IMU, and camera data for robust state estimation in challenging environments.

## Technical Specifications

**Method Type:** Optimization-based approach

**Causality:** Yes, the method is causal

**Bundle Adjustment:** No

**Loop Closure:** Yes

**Sensor Configuration:** LiDAR, mono, and IMU

**Processing Performance:** Average processing time: ~50ms per frame

**Parameter Consistency:** Yes

**Manual Alignment:** No