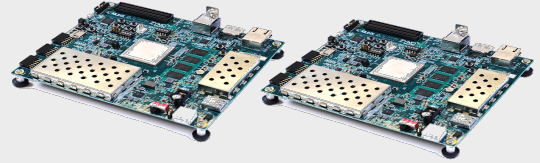Evaluation System with Multi-robot ROS
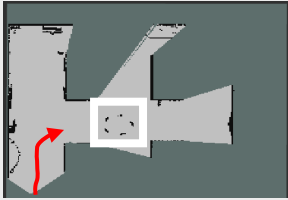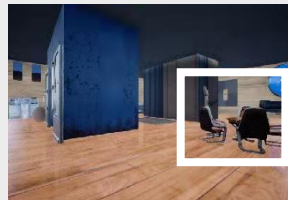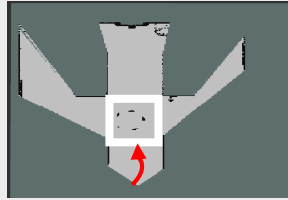
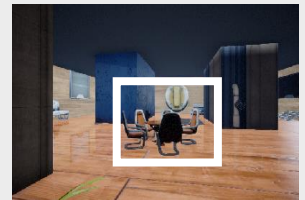AirSim simulator with ROS Communicate with ROS ZCU102 board with ROS and INCA

(a) Evaluation System based on multi-agent ROS. The AirSim simulator runs on the server. The computation runs on ZCU102 boards.
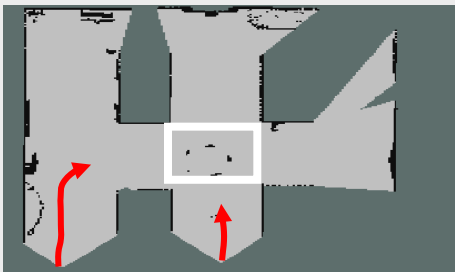
VO results with SuperPoint (Local map and trajectory) Input images for PR of the same scene (chairs in white boxes)

(b) The map and trajectory are generated by VO based on FE. The two input pictures are from the same scene are described and matched.

Merged Map → Robot Tasks on : Exploration/ Navigation/ ...

(c) Maps are merged via the same scene for further robot tasks.