Deschaud JE, 2018. IMLS-SLAM: scan-to-model matching based on 3D data. IEEE Int Conf on Robotics and Automation, p.2480-2485. https://doi.org/10.1109/ICRA.2018.8460653

Engel J, Sch?ps T, Cremers D, 2014. LSD-SLAM: Large-scale direct monocular SLAM. Proc 13th European Conf on Computer Vision, p.834-849. https://doi.org/10.1007/978-3-319-10605-2_54

Engel J, Koltun V, Cremers D, 2018. Direct sparse odometry. *IEEE Trans Pattern Anal Mach Intell*, 40(3):611-625. https://doi.org/10.1109/TPAMI.2017.2658577

Forster C, Pizzoli M, Scaramuzza D, 2014. SVO: fast semi-direct monocular visual odometry. IEEE Int Conf on Robotics and Automation, p.15-22. https://doi.org/10.1109/ICRA.2014.6906584

Forster C, Carlone L, Dellaert F, et al., 2017. On-manifold preintegration for real-time visualĺCinertial odometry. *IEEE Trans Robot*, 33(1):1-21. https://doi.org/10.1109/TRO.2016.2597321

Geiger A, Lenz P, Stiller C, et al., 2013. Vision meets robotics: the KITTI dataset. *Int J Robot Res*, 32(11): 1231-1237. https://doi.org/10.1177/0278364913491297

Grisetti G, Stachniss C, Burgard W, 2007. Improved techniques for grid mapping with Rao-Blackwellized particle filters. *IEEE Trans Robot*, 23(1):34-46. https://doi.org/10.1109/TRO.2006.889486

Hemann G, Singh S, Kaess M, 2016. Long-range GPS-denied aerial inertial navigation with lidar localization. IEEE/RSJ Int Conf on Intelligent Robots and Systems, p.1659-1666. https://doi.org/10.1109/IROS.2016.7759267

Hess W, Kohler D, Rapp H, et al., 2016. Real-time loop closure in 2D LIDAR SLAM. IEEE Int Conf on Robotics and Automation, p.1271-1278. https://doi.org/10.1109/ICRA.2016.7487258

Kerl C, Sturm J, Cremers D, 2013. Dense visual SLAM for RGB-D cameras. IEEE/RSJ Int Conf on Intelligent Robots and Systems, p.2100-2106. https://doi.org/10.1109/IROS.2013.6696650

Kim G, Park B, Kim A, 2019. 1-day learning, 1-year localization: long-term LIDAR localization using scan context image. *IEEE Robot Automation Lett*, 4(2):1948-1955. https://doi.org/10.1109/LRA.2019.2897340

Klein G, Murray D, 2007. Parallel tracking and mapping for small AR workspaces. Proc 6th IEEE and ACM Int Symposium on Mixed and Augmented Reality, p.1-10. https://doi.org/10.1109/ISMAR.2007.4538852

Konolige K, Grisetti G, Kĺźmmerle R, et al., 2010. Efficient sparse pose adjustment for 2D mapping. IEEE/RSJ Int Conf on Intelligent Robots and Systems, p.22-29. https://doi.org/10.1109/IROS.2010.5649043

Lee J, Hwang S, Lee K, et al., 2020. AD-VO: scale-resilient visual odometry using attentive disparity map. https://arxiv.org/abs/2001.02090

Maurer CR, Qi RS, Raghavan V, 2003. A linear time algorithm for computing exact Euclidean distance transforms of binary images in arbitrary dimensions. *IEEE Trans Pattern Anal Mach Intell*, 25(2):265-270. https://doi.org/10.1109/TPAMI.2003.1177156

Mur-Artal R, Tardós JD, 2017. ORB-SLAM2: an open-source SLAM system for monocular, stereo, and RGB-D cameras. *IEEE Trans Robot*, 33(5):1255-1262. https://doi.org/10.1109/TRO.2017.2705103

Mur-Artal R, Montiel JMM, Tardĺős JD, 2015. ORB-SLAM: a versatile and accurate monocular SLAM system. *IEEE Trans Robot*, 31(5):1147-1163. https://doi.org/10.1109/TRO.2015.2463671

Nair GB, Daga S, Sajnani R, et al., 2020. Multi-object monocular SLAM for dynamic environments. https://arxiv.org/abs/2002.03528

Newcombe RA, Lovegrove SJ, Davison AJ, 2011. DTAM: dense tracking and mapping in real-time. Int Conf on Computer Vision, p.2320-2327. https://doi.org/10.1109/ICCV.2011.6126513

Patel N, Khorrami F, Krishnamurthy P, et al., 2019. Tightly coupled semantic RGB-D inertial odometry for accurate long-term localization and mapping. Proc 19th Int Conf on Advanced Robotics, p.523-528. https://doi.org/10.1109/ICAR46387.2019.8981658

Rusinkiewicz S, Levoy M, 2001. Efficient variants of the ICP algorithm. Proc 3rd Int Conf on 3-D Digital Imaging and Modeling, p.145-152. https://doi.org/10.1109/IM.2001.924423

Shao WZ, Vijayarangan S, Li C, et al., 2019. Stereo visual inertial LiDAR simultaneous localization and mapping. IEEE/RSJ Int Conf on Intelligent Robots and Systems, p.370-377. https://doi.org/10.1109/IROS40897.2019.8968012

Sibley G, Matthies L, Sukhatme G, 2010. Sliding window filter with application to planetary landing. *J Field Robot*, 27(5):587-608. https://doi.org/10.1002/rob.20360

Sünderhauf N, Neubert P, Protzel P, 2013. Predicting the changeĺCa step towards life-long operation in everyday environments. Robotics Challenges and Vision.

Wagstaff B, Peretroukhin V, Kelly J, 2020. Self-supervised deep pose corrections for robust visual odometry. IEEE Int Conf on Robotics and Automation, p.2331-2337. https://doi.org/10.1109/ICRA40945.2020.9197562

Wang ZJ, Wu Y, Niu QQ, 2020. Multi-sensor fusion in automated driving: a survey. *IEEE Access*, 8:2847-2868. https://doi.org/10.1109/ACCESS.2019.2962554

Xu YL, Ou YS, Xu TT, 2018. SLAM of robot based on the fusion of vision and LIDAR. IEEE Int Conf on Cyborg and Bionic Systems, p.121-126. https://doi.org/10.1109/CBS.2018.8612212

Zhang J, Singh S, 2015. Visual-lidar odometry and mapping: low-drift, robust, and fast. IEEE Int Conf on Robotics and Automation, p.2174-2181. https://doi.org/10.1109/ICRA.2015.7139486

Zhao HJ, Chiba M, Shibasaki R, et al., 2008. SLAM in a dynamic large outdoor environment using a laser scanner. IEEE Int Conf on Robotics and Automation, p.1455-1462. https://doi.org/10.1109/ROBOT.2008.4543407

Zhao ZR, Mao YJ, Ding Y, et al., 2019. Visual-based semantic SLAM with landmarks for large-scale outdoor environment. Proc 2nd China Symposium on Cognitive Computing and Hybrid Intelligence, p.149-154. https://doi.org/10.1109/CCHI.2019.8901910

Zhu XR, Qiu CX, Deng FC, et al., 2017. Cloud-based real-time outsourcing localization for a ground mobile robot in large-scale outdoor environments. *J Field Robot*, 34(7):1313-1331. https://doi.org/10.1002/rob.21712