

Odometry with OKVIS [1] in stereo mode (VIO). Visual features from SuperPoint + SuperGlue [2]. Loop closure, map alignment and full bundle adjustment with maplab [3,4] using the visual features (on all available camera) and IMU.

Comments:

- Multi-session alignment was fully automatic. A few times had to increase search time when one of the maps failed to align with the default parameters.
- Re-calibrated camera intrinsics online to improve scale drift for final step.
- OKVIS parameters were tuned separately for the different environments.

Total processing time (Intel i7-8700, 32GB of RAM, Nvidia GTX 1080 Ti) was around 2 days for the entire dataset with a linearly proportional relationship in time.