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define_new_keyframe Done. New KF #0 with 0 new edges.  
Created KF #0 : # kf-to-kf edges created:0  
Optimization error: 0 -> 0
```

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=====  
[OPT] LM: Initial RMSE=0.908096 #Jchs=26 #k2k_edges=1 #k2f_edges=0 #obs=26  
[OPT] Final RMSE=0.000308303 #iters=5  
[OPT] LM: Initial RMSE=0.000218003 #Jchs=78 #k2k_edges=1 #k2f_edges=26 #obs=52  
[OPT] Final RMSE=0.000128834 #iters=7  
[define_new_keyframe] Done. New KF #1 with 1 new edges.  
Created KF #1 : # kf-to-kf edges created:1  
Optimization error: 2.47133e-006 -> 8.63101e-007  
=====
```

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Inv_pose of KF-to-KF edge #0 (relative pose of KF#0 wrt KF#1):  
(x,y,z,yaw,pitch,roll)=(-1.2315,-0.2911,-0.0059,9.84deg,-0.22deg,0.82deg)  
Relative pose of KF#1 wrt KF#0:  
(x,y,z,yaw,pitch,roll)=(1.2632,0.0762,0.0000,-9.85deg,0.08deg,-0.84deg)  
Ground truth: relative pose of KF#1 wrt KF#0:  
(x,y,z,yaw,pitch,roll)=(1.2632,0.0763,0.0000,-9.84deg,0.07deg,-0.84deg)  
Saving final graph of KFs and LMs to: graph.dot  
Done.  
Press any key or close window to exit.
```

VR
PT RBA results

