Structureless Pose-Graph Loop-Closure with a Multi-Camera System on a Self-Driving Car

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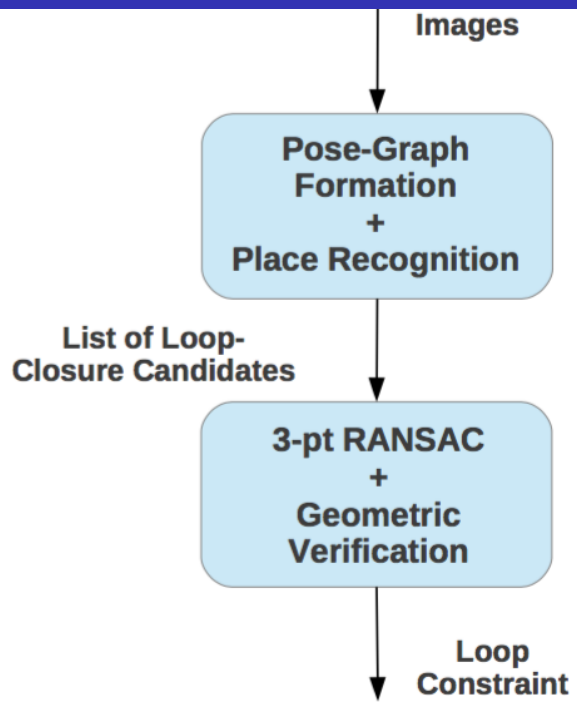

- Proposes a method to compute the pose-graph loop-closure constraints using multiple overlapping field-of-views cameras mounted on a self-driving car
- Contributions:
  - Shows that the relative pose for the loop-closure constraint can be computed directly from the epipolar geometry of a multi-camera system
  - Avoids the additional time complexities from the reconstruction of 3D scene points
  - Provides greater flexibility in choosing a configuration for the multi-camera system to cover a wider field-of-view to avoid missing out any loop-closure opportunities
- Evaluates on ParkingGarage01, ParkingGarage02 and Campu01 datasets