A Robust Client-Server Architecture for Map Information Processing and Transmission for Distributed Visual SLAM

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- It is important to share maps with each other from the perspective of swarm robotics

- This paper develops a client-server system for ORB-SLAM2

- Split the components of the map into minimum units and send them separately

- Two wirelessly connected computers can share the same map in real time

- Key frames and map points will be shared without latency in a faster communication environment.
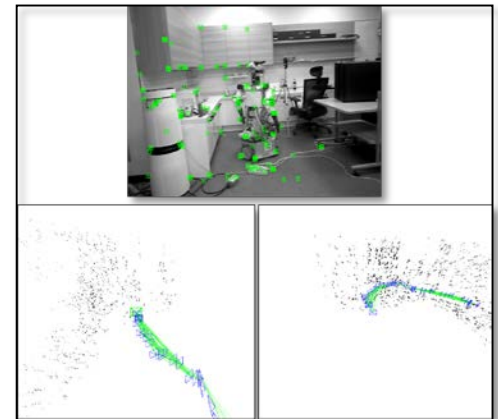
Process of mapping the physical environment in client and server map