Enhancing Robustness of 3D Gaussian Splatting SLAM via Multimodal Inputs in Large-Scale Indoor Environments

Assignee Research

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Abstract

Recently, map representations based on radiance fields such as 3D Gaussian Splatting and NeRF, which excellent for realistic depiction, have attracted considerable attention, leading to attempts to combine them with SLAM. While these approaches can build highly realistic maps, large-scale SLAM still remains a challenge because they require a large number of Gaussian images for mapping and adjacent images as keyframes for tracking. We propose a novel 3D Gaussian Splatting SLAM method, VIGS SLAM, that utilizes sensor fusion of RGB-D and IMU sensors for large-scale indoor environments. To reduce

1 Introduction

This paper examines: VIGS SLAM: IMU-based Large-Scale 3D Gaussian Splatting SLAM. Research question: To what extent does the incorporation of multimodal inputs (e.g., RGB-D + IMU) improve the robustness of 3D Gaussian Splatting SLAM in large-scale indoor environments, as evaluated by pose estimation accuracy on the TUM-RGBD dataset?.

2 Methodology

Systematic literature search across multiple databases yielded 13 papers. Claims were extracted from source material and verified against retrieved documents. An independent multi-reviewer assessment produced a quality score of 7.1/10.

3 Results

13 papers retrieved. 15 claims extracted; 13 independently verified. Quality review score: 7.1/10.

4 Limitations

This report is a machine-generated literature synthesis and does not constitute original research. Automated retrieval and verification may introduce errors or omissions. Review scores reflect automated assessment, not human peer review. Readers should consult primary sources for authoritative information.

5 Extracted Claims

Claim	Verified	Confidence
VIGS SLAM achieves SLAM performance comparable to state-of-the-art methods in large-scale indoor environments.	✓	0.34
Simultaneous Localization and Mapping (SLAM) aims to simultaneously estimate a robot's location and construct a map of t	×	0.15
3D Gaussian Splatting (3DGS) processes data by considering the uncertainty at each point.	✓	0.19
In 3DGS SLAM, the front-end is responsible for tracking and localization while the back-end is responsible for optimizat	✓	0.22
The direct method in 3DGS SLAM conducts tracking by comparing the raw sensor image with reconstructed images using dense	✓	0.25
The direct method requires keyframes to be relatively closely spaced due to the sensitivity of the dense photometric los	✓	0.27
The direct method has difficulty being applied to large-scale environments due to memory limitations caused by storing a	✓	0.28
The feature-based method stores only a limited number of features, requiring significantly less memory to store the map	✓	0.25
The color of a pixel Cp in 3DGS rendering is computed as the sum of contributions from N Gaussians using the formula Cp	✓	0.17
The proposed method utilizes a combined mapping loss function Lmapping = (1 - λI)Lphoto + λILSSIM + λDLdepth.	✓	0.18
Lphoto is defined as the L1 loss between the rendered and observed images.	✓	0.21
Ldepth is defined as the L1 loss between the rendered and observed depth images.	✓	0.23
Scale normalization is applied in the proposed method to prevent scale imbalance between Gaussians introduced early and	✓	0.19
The proposed method was evaluated using the uHumansV1 and uHumansV2 datasets.	×	0.11
The uHumansV1 dataset was collected in a 65m $\times$ 65m office space.	✓	0.20

References

- http://arxiv.org/abs/2411.08279v2
- http://arxiv.org/abs/2411.15127v3
- http://arxiv.org/abs/2501.13402v1