

Peer Review

Review of: "[Withdrawn] AirIO: Learning Inertial Odometry with Enhanced IMU Feature Observability — air-io.github.io"

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This paper proposed an interesting learned inertial odometry framework with body-frame represented IMU data. The methods are well explained, and the experimental results are solid to support the contribution claims. I have the following comments that might be helpful to improve the paper.

Full name and reference to t-SNE should be presented in the first contribution claim.

Full name of HACF in the second paragraph of Section III should be provided.

After Equation (2), the authors claim that the rotation obtained by the simple IMU is accurate enough; is that true? Does it mean in the short term?

In Figure 7, is the AirIMU network only used to output the filtered IMU data and not to simultaneously predict the robot state?

In Section V-A, the second paragraph, "As shown in 10" should be "As shown in Fig. 10".

Declarations

Potential competing interests: No potential competing interests to declare.