

RGB-D SLAM

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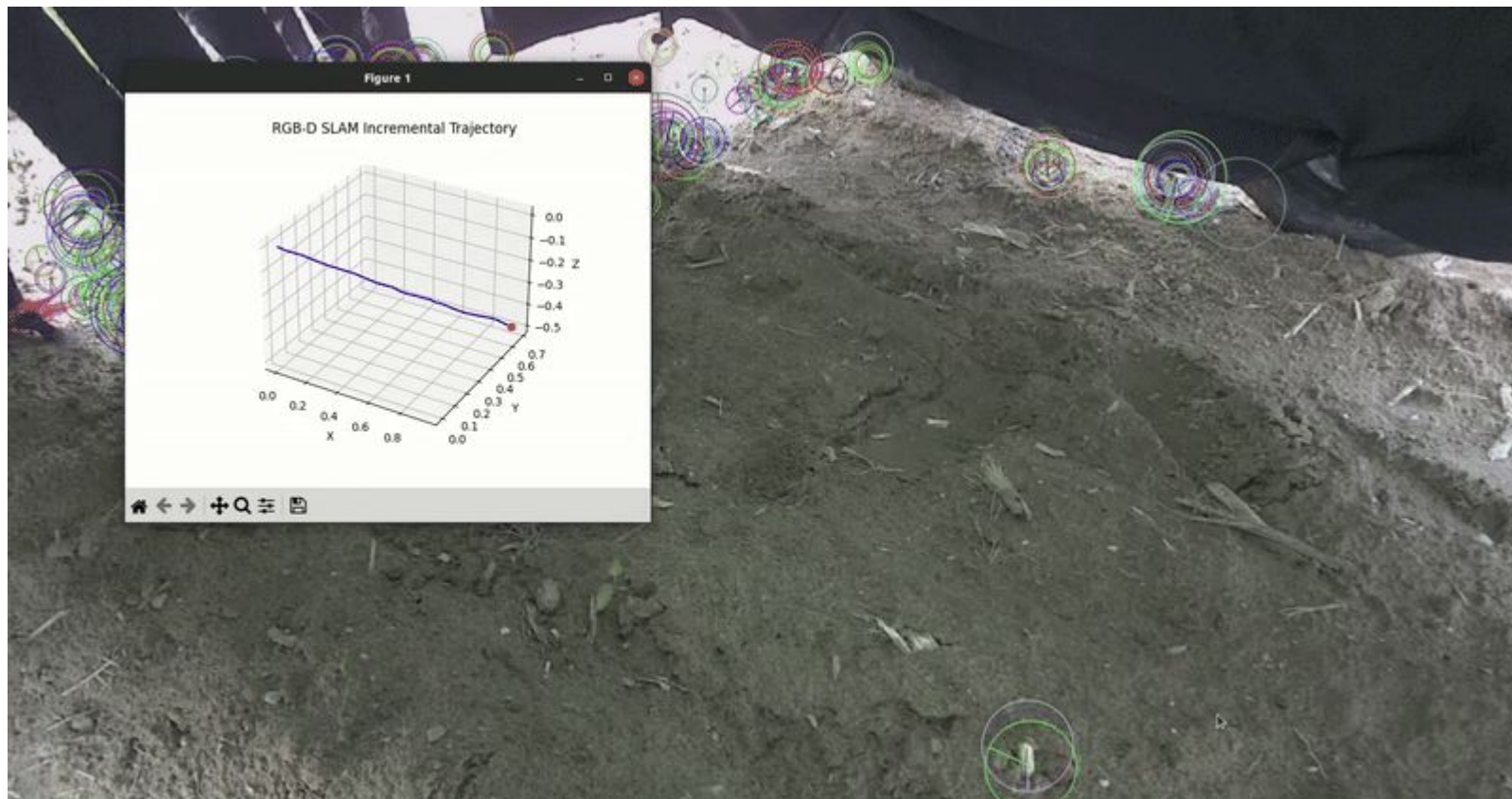
Method Used

- RGB-D Visual SLAM
- Feature Extraction: ORB Feature Extraction
- Feature Matching: Brute Force Hamming Matching
- Reconstruction: Backprojecting depth
- Pose Estimation: PnP RANSAC
- Incremental Trajectory Accumulation

ORB Features



Without Z constraint



With Z hard constraint

