Topic	GitHub repository	Paper	Work	Comment
CNN Slam	https://github.com/iitmcvg/CNN_SLAM	https://arxiv.org/abs/1704.03489	Produced depth images from Monocular images using CNN. Output images needed to be processed (resolution and image type) to be applied to RTABMap.	Slow to produce the depth images. Applied to RTABMap, but result was not satisfactory. The repo uses very old versions of python (2.x) and Tensorflow(1.14).
RTABMap	https://github.com/introlab/rtabmap/wiki	--	Installed RTABMap application, run some tutorials, used the TUM dataset (RGB and Depth images are given, taken from Kinect), calibrated camera and created point cloud.	If the appropriate depth images are given, easy to implement. Not applicable for Monocular images.
Self-supervised Monocular depth prediction	https://github.com/nianticlabs/monodepth2	https://arxiv.org/abs/1806.01260	Produced depth images from monocular images. Needed to be pre-processed to apply to RTABMap.	Faster and better result than CNN slam. Applied to RTABMap, result was not satisfactory. Uses comparatively newer version of libraries w.r.t. CNN slam.
Monocular Depth Estimation using Zero-shot Cross-dataset Transfer	https://github.com/islorg/MiDaS	https://arxiv.org/abs/1907.01341v3	Produced depth images using different types of mentioned models and observed their result from RTABMap. No need to pre-process.	Fastest, most recent and producing the best result. Though the RTABMap result was better than the previous two, not satisfactory in general, too many misplaced points.
PUTSLAM	https://github.com/LRMPUT/PUTSLAM	--	Tried to create point cloud. At first, tried with colab and then, installed older version of ubuntu as virtual machine.	This repo is 5 years older and the ubuntu version they used is 14.04. Too many version and module errors.

Table.1 - Documentation on Progress