ORB-SLAM

we will use the latest version, ORB-SLAM 3 developed by UZ-SLAMLab:

@article{ORBSLAM3\_TRO,

title={{ORB-SLAM3}: An Accurate Open-Source Library for Visual, Visual-Inertial

and Multi-Map {SLAM}},

author={Campos, Carlos AND Elvira, Richard AND G\´omez, Juan J. AND Montiel,

Jos\'e M. M. AND Tard\'os, Juan D.},

journal={IEEE Transactions on Robotics},

volume={37},

number={6},

pages={1874-1890},

year={2021}

}

There is an unofficial windows version, however since Linux is almost easier to use in such cases, we’ve decided to download it for Linux, specifically, Ubuntu as this is the distro that’s officially supported. To do this, we’ve created a VM using Oracle’s VirtualBox (the choosing between this and vmware or something else is arbitrary at the moment). After creating a shared folder between the (Ubuntu) VM guest and the (Windows) host, we’ve started installing ORB-SLAM 3 following “MH Yip”’s tutorial on [YouTube](https://youtu.be/DxqzwBQVCNw?si=BMY0lmGnyQJ_D5rx) and [GitHub](https://github.com/Mauhing/ORB_SLAM3/) repo. However, since we’re working in Ubuntu 22.04 there were some compatibility problems with the above guides. After further research we found another [guide](https://gist.github.com/bharath5673/4295e666cbe654a83226a2549a972c4f) on GitHub. Using this guide we were able to