

Weekly Report

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Topic: Robot Guided Surface Scanning with Ultrasound

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Tasks Done:

- I have implemented ICP algorithm using 2 different methods.
- Both yield good results
- 1st method matches the points plane wise
- 2nd method uses the distance ratio and then use only the matched points to get the transformation
- Translation in x, y, z is achieved with good accuracy.
- Also, I think rotation along x and y direction also works well.
- But I am not sure about the rotation along z axis.



