**ORB\_SLAM配置**

**1、安装工具**

sudo apt-get install libboost-all-dev libblas-dev liblapack-dev

**2、依赖性安装 Pangolin**

# Required

# OpenGL (Desktop / ES / ES2)

sudo apt install libgl1-mesa-dev

# Glew

sudo apt install libglew-dev

# CMake

sudo apt install cmak

# Recommended

# Python2 / Python3, for drop-down interactive console

sudo apt install libpython2.7-dev

# Wayland

sudo apt install pkg-config

sudo apt install libegl1-mesa-dev libwayland-dev libxkbcommon-dev wayland-protocols

# Optional

# FFMPEG (For video decoding and image rescaling)

sudo apt install ffmpeg libavcodec-dev libavutil-dev libavformat-dev libswscale-dev libavdevice-dev

# DC1394 (For firewire input)

sudo apt install libdc1394-22-dev libraw1394-dev

# libuvc (For cross-platform webcam video input via libusb)

git://github.com/ktossell/libuvc.git

# libjpeg, libpng, libtiff, libopenexr (For reading still-image sequences)

sudo apt install libjpeg-dev libpng-dev libtiff5-dev libopenexr-dev

# 以上依赖除了Required项，其他的可以自己选装，对ORBSLAM2的编译影响不大

# build and install

git clone https://github.com/stevenlovegrove/Pangolin.git

cd Pangolin

mkdir build

cd build

cmake ..

make

sudo make install

**3、安装eigen3**

sudo apt-get install libeigen3-dev

**4、编译**

git clone https://github.com/raulmur/ORB\_SLAM2.git ORB\_SLAM2

cd ORB\_SLAM2

chmod +x build.sh

./build.sh

**启动单目SLAM示例**

roscore

rosrun ORB\_SLAM2 Mono Vocabulary/ORBvoc.txt Examples/ROS/ORB\_SLAM2/Asus.yaml

rosbag play rgbd\_dataset\_freiburg1\_desk.bag /camera/rgbd/image\_color:=/camera/image\_raw