University of Burgundy

Software Engineering Project Weekly Report

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1 Task completed

A previous captured RGB and depth map (retrieved by using Kinect with OpenNI and OpenCV libraries) were provided. Based on that, the following tasks were accomplished:

- Using the data from the RGB and depth images a colored pointcloud was generated. For this purpose, the x, y and z values are calculated for each point (z comes from the depth pixel).

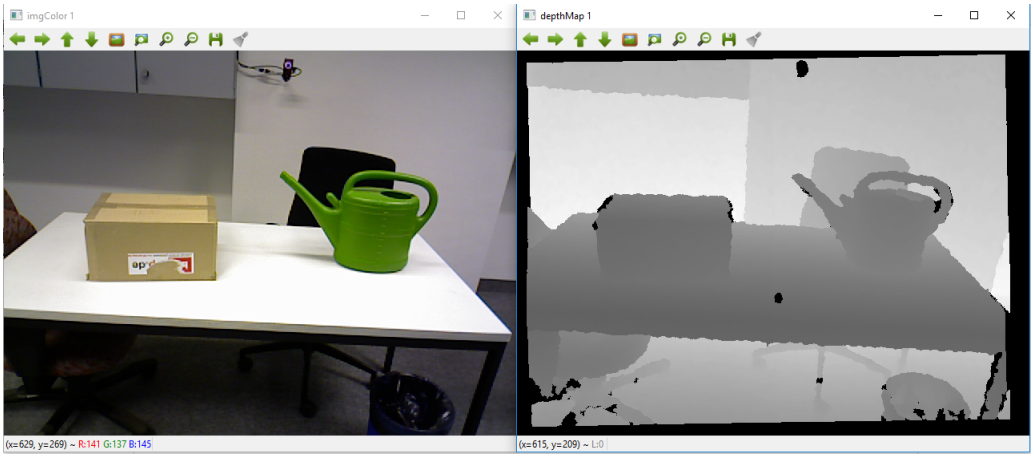

Figure 1: RGB and depth images

- Displaying the point cloud using PCL library.

Figure 2: PCL Viewer

2 Work in progress

The main task in progress is to capture our own images using OpenNI and OpenCV libraries; however there is a problem because at the moment the Kinect is not being recognized.

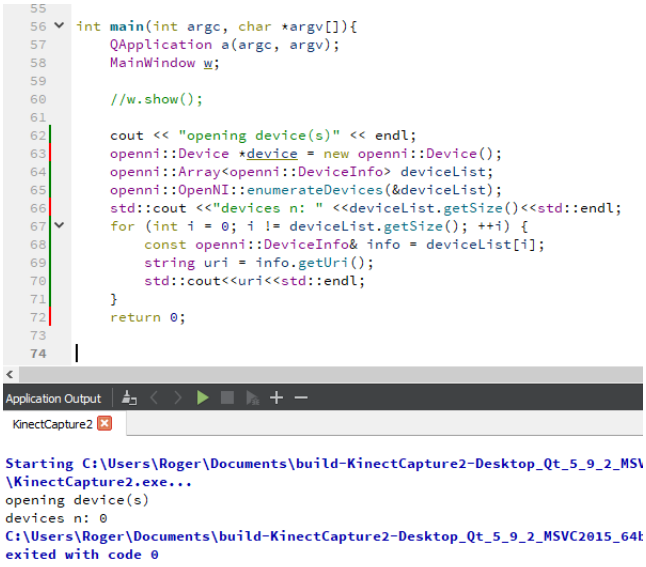

Figure 3: Kinect capture

After being able to capture images, we will be able to work on identification of key points, extraction of features for those keypoints and correspondences estimation.