**Slam Team Progress Report**

**Franklin Snider**: I am working on the **loop closure**. I have just been trying to get a clear understanding of how it is done this week so no coding yet. I am still trying to learn about the ellipse matching in the smith paper I added to the repository, as well as how to correct the pose graph when two ellipses overlap.

**John Francis:** I am working on implementing the Kalman filters. I completed the code for the altitude Kalman filter that uses the IMU acceleration and laser range finder measurements to estimate the altitude. Currently, I am reading the ICRA 2014 paper to understand how to implement the pose estimation unscented Kalman filter (UKF). I do not think the actual code for the UKF will be too extensive, but the UKF discussion pulls information from several other papers so I am working my way through them now.