

# Weekly Report

## 6/28 – 7/4

- Made several webcam calibrations for testing.
- Tested webcam calibrations with ORB-SLAM2 lib.
  - Found one calibration works better.
  - Graphs are clearer now - red and black points are both map points, where red points are current local map points; blue frames are key frames, which are selected frames for estimating the map; green line is the trajectory of camera.
  - Some factors affect the tracking of ORB features such as light and moving too fast.

Plans for next week:

- Keep studying ORB-SLAM
- Test on Raspberry Pi