# A first example

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# Outline

# Introduction

# What is SLAM ?

SLAM stands for ...

# Problem

- Computational Heavyness
- High Theoretical Complexity
- How to pratically do it ?

# Proposed solution

ProSlam:

- light
- simple
- clear

# Big Picture

# Story

- LSD SLAM
- etc

# State of the art

- ORB SLAM 2
- etc

# Main contribution

ProSlam:

- open source cpp implementation
- easy to use for beginners...
- computationally light
- good performances

# Methods

# SLAM Map

location based graph ... **Loop:**

- Relocation
- Adjustment

# Pipeline

Core Modules:

- Triangulation
- Incremental Motion Estimation
- Map Management
- Relocation

# Triangulation

....

# Triangulation : Intuition

img of the fact that correspondences are expected only on one side of the other image and they can also be sorted with euclidean distance metric

# Incremental Motion Estimation

....

# Map Management

Three main steps :

- Correspondence recovery
- Landmark optimization
- Local map generation

# Relocation

....

# Data Structs

- KeyPoint
- FramePoint
- Frame
- LandMark
- LocalMap
- GlobalMap

# Results

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... images of plots and performances .. benchmarks

# Conclusion

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In the end:

- summmarizing implications of the results
- connect results with provided claims
- take home message