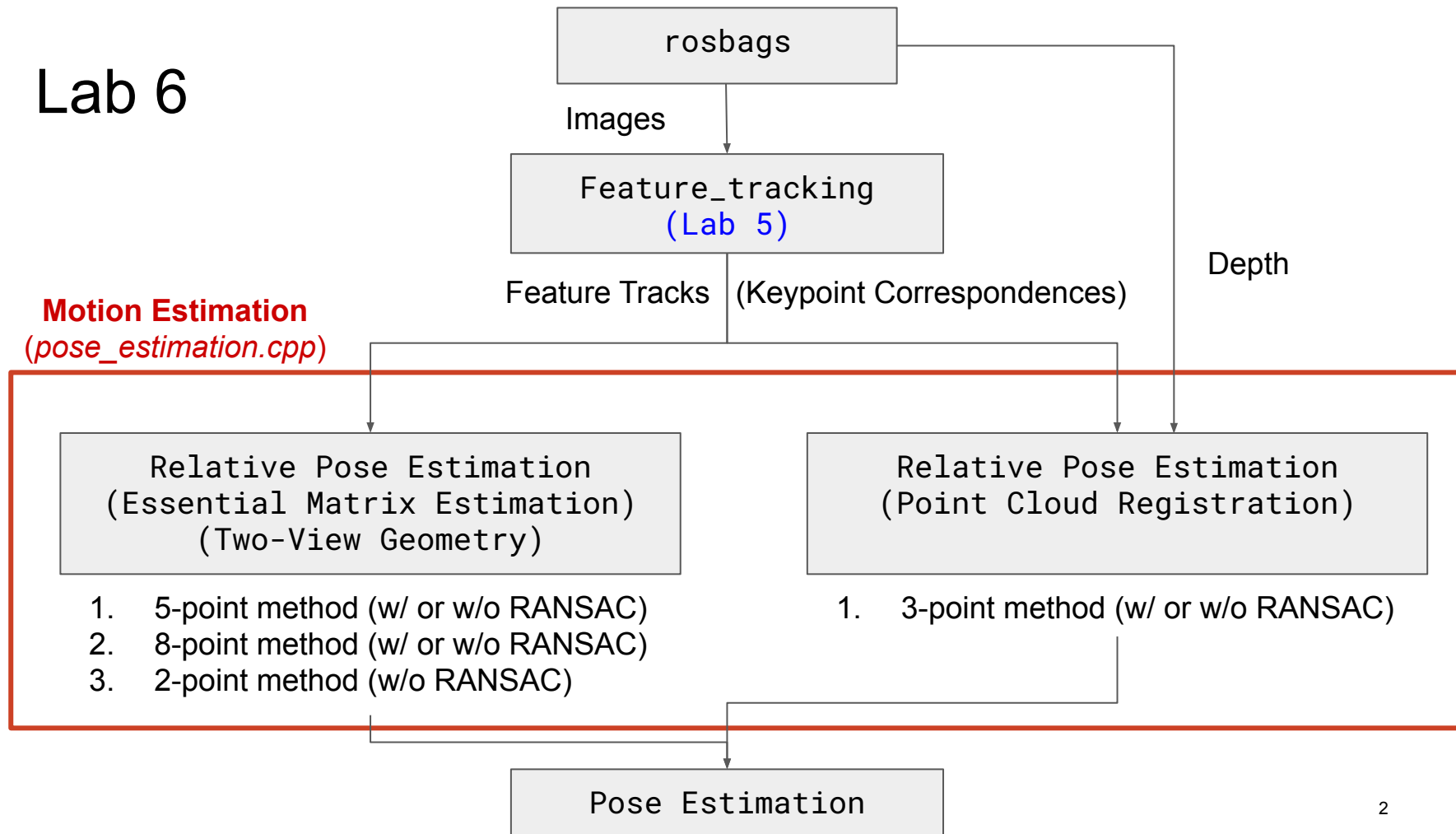


Lab 6: Vision-based Motion Estimation

VNAV 2020

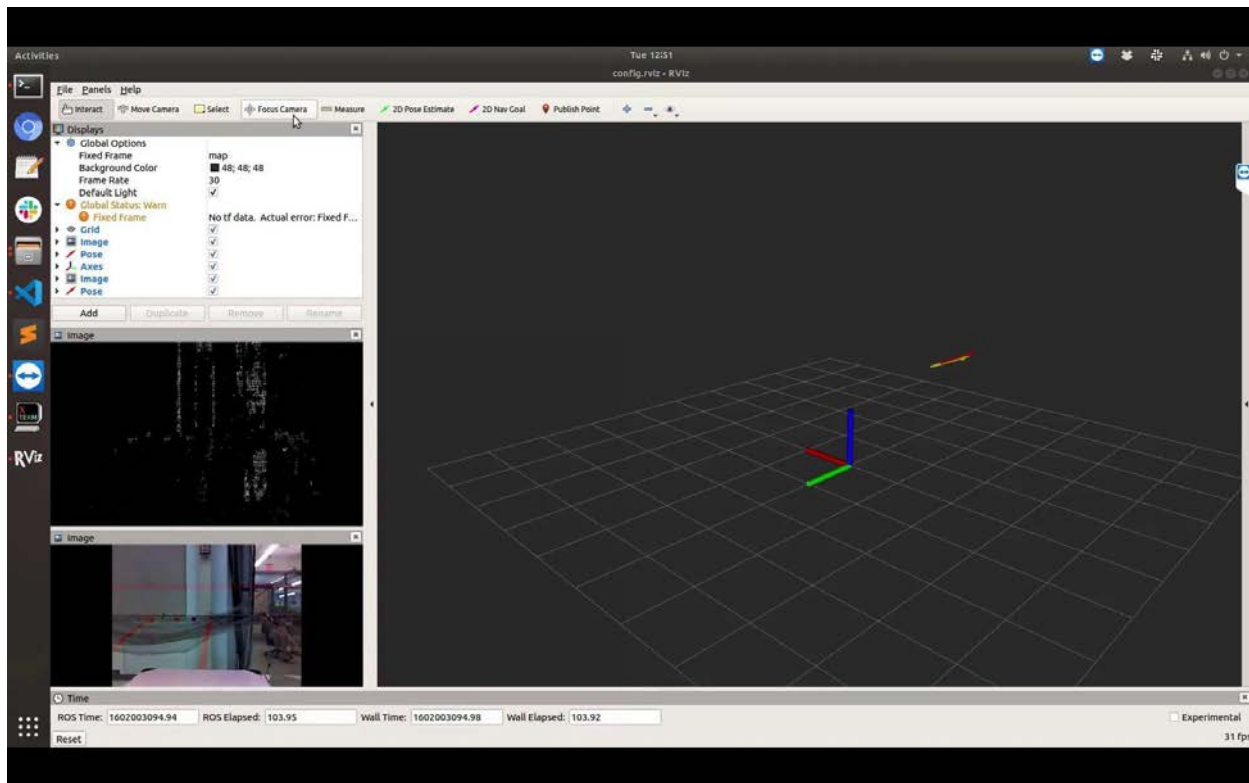
Lab 6



Example: 3-point Method

The visualization uses ground-truth poses.

The trajectory will quickly **drift** if we simply concatenate RANSAC relative estimates.



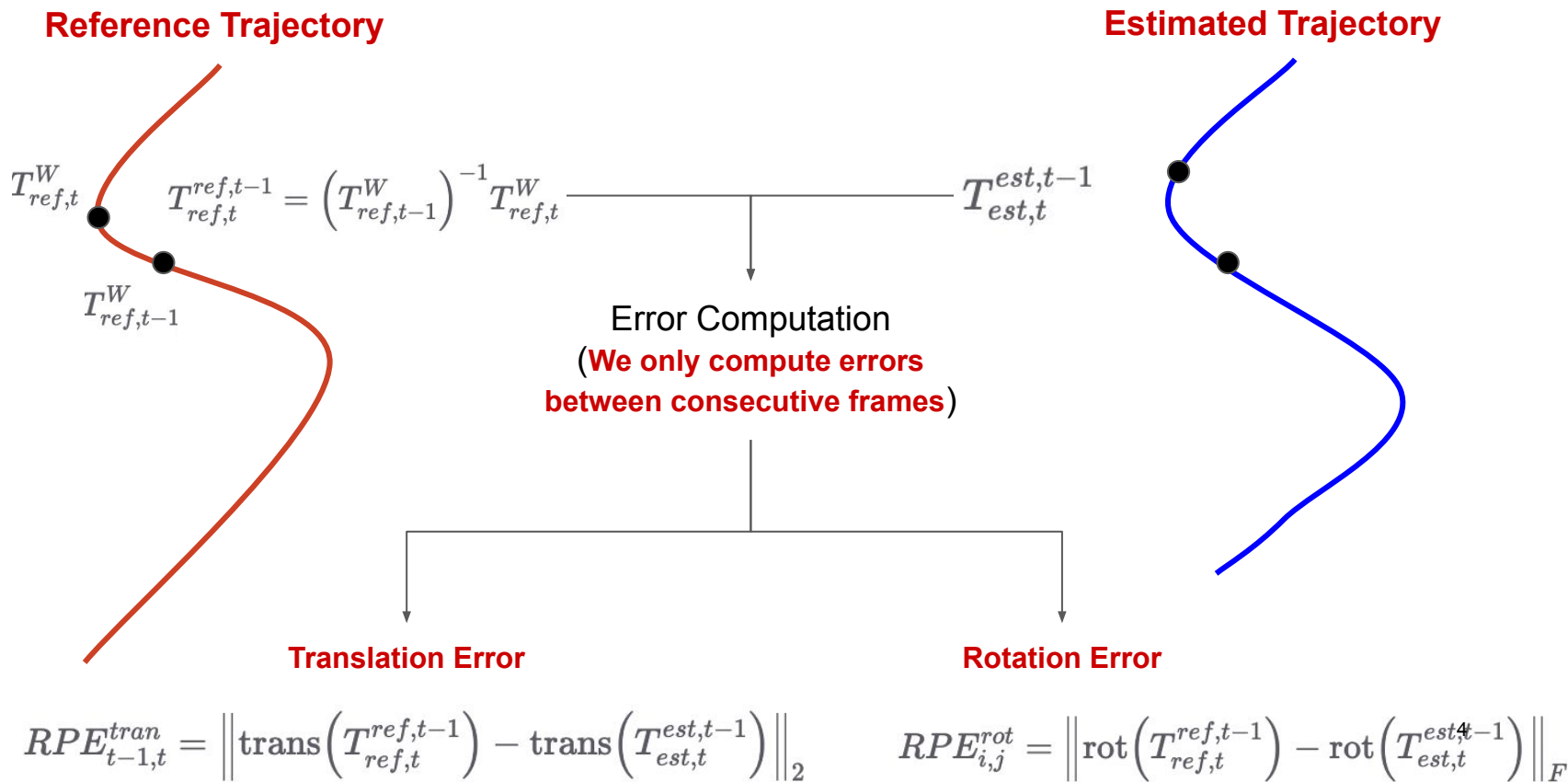
Depth

Images

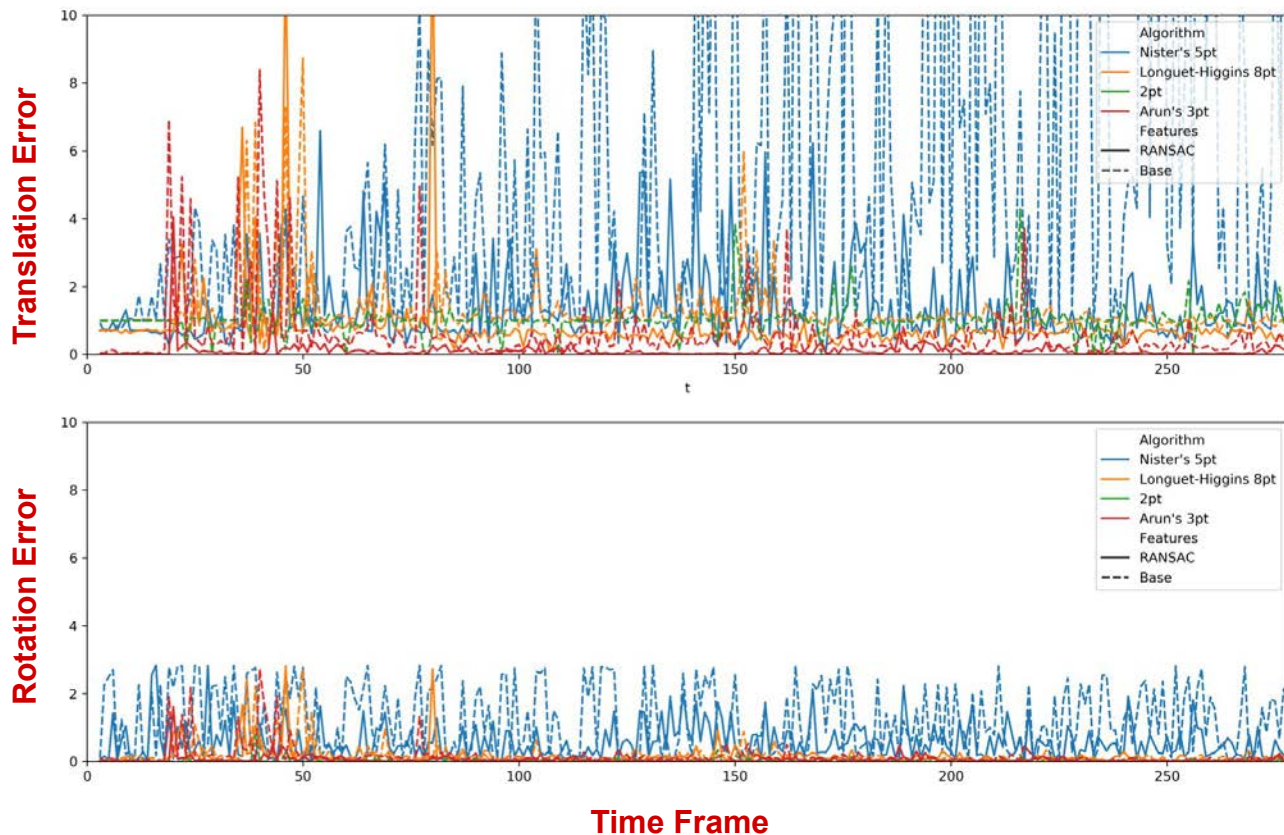
Red arrow:
GT pose

Yellow arrow:
Estimated pose

Evaluate the Performance of Algorithms



Submission: Plots of the Statistics



<https://mit-spark.github.io/VN/AV2020-handouts/lab6/>

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16.485 Visual Navigation for Autonomous Vehicles (VNAV)
Fall 2020

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