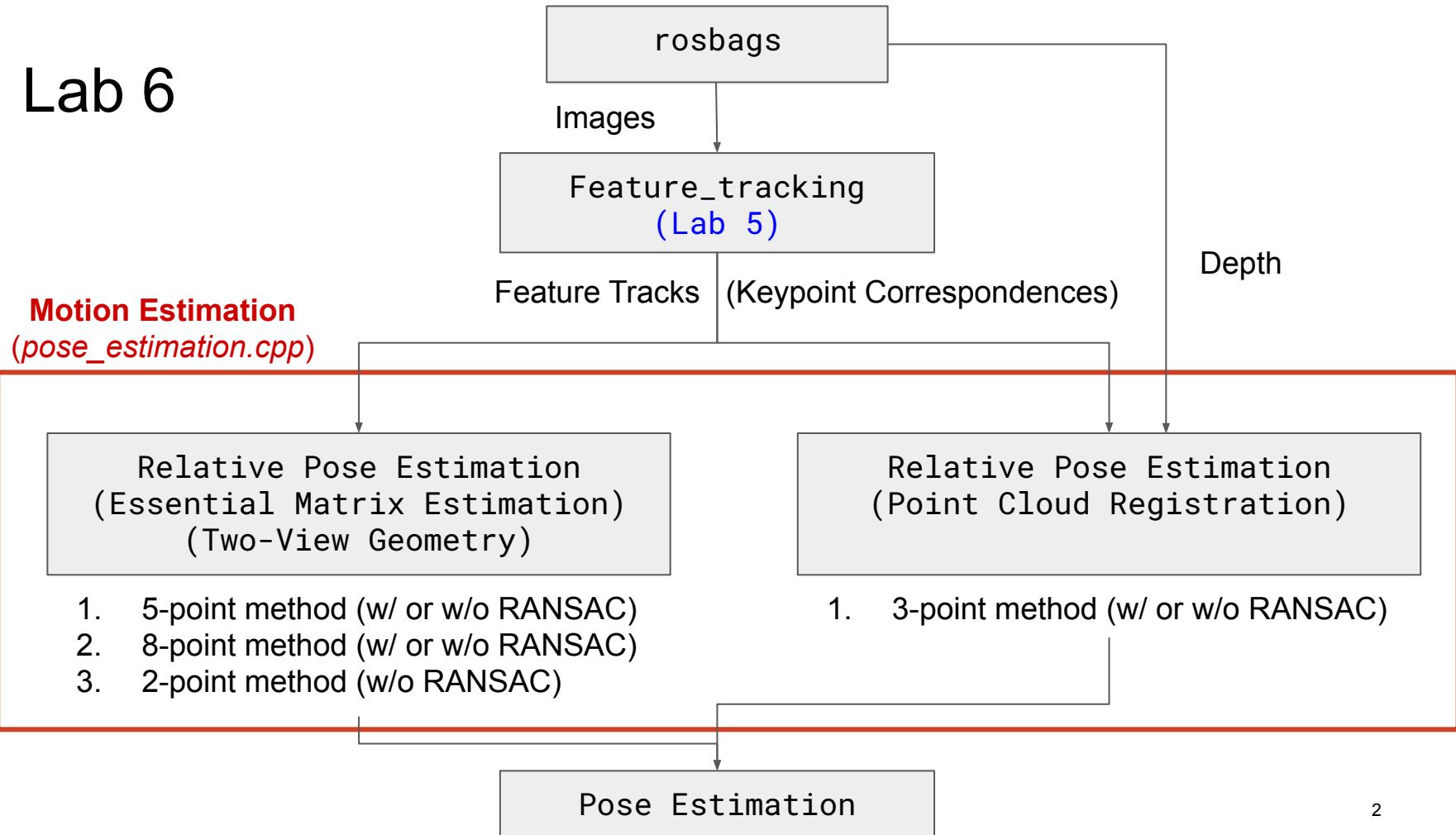


## Lab 6: Vision-based Motion Estimation

VNAV 2020

# Lab 6



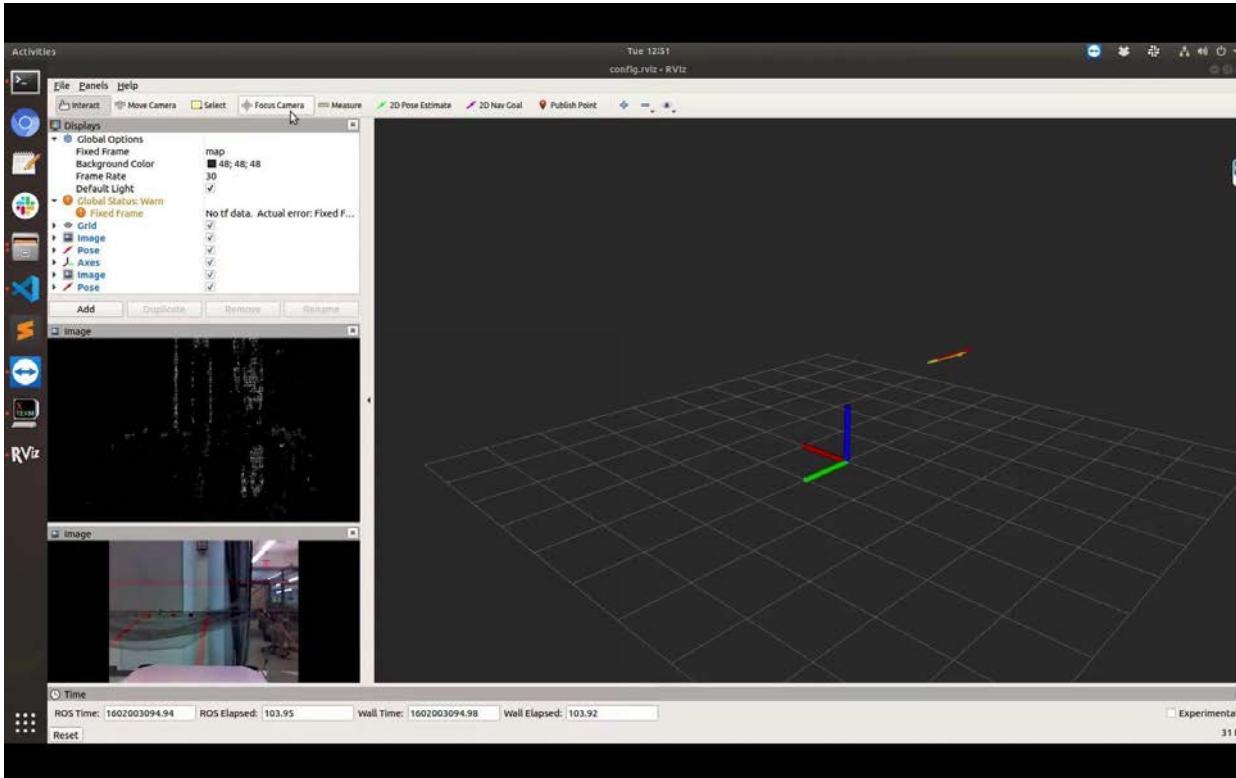
# Example: 3-point Method

The visualization uses ground-truth poses.

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

Depth

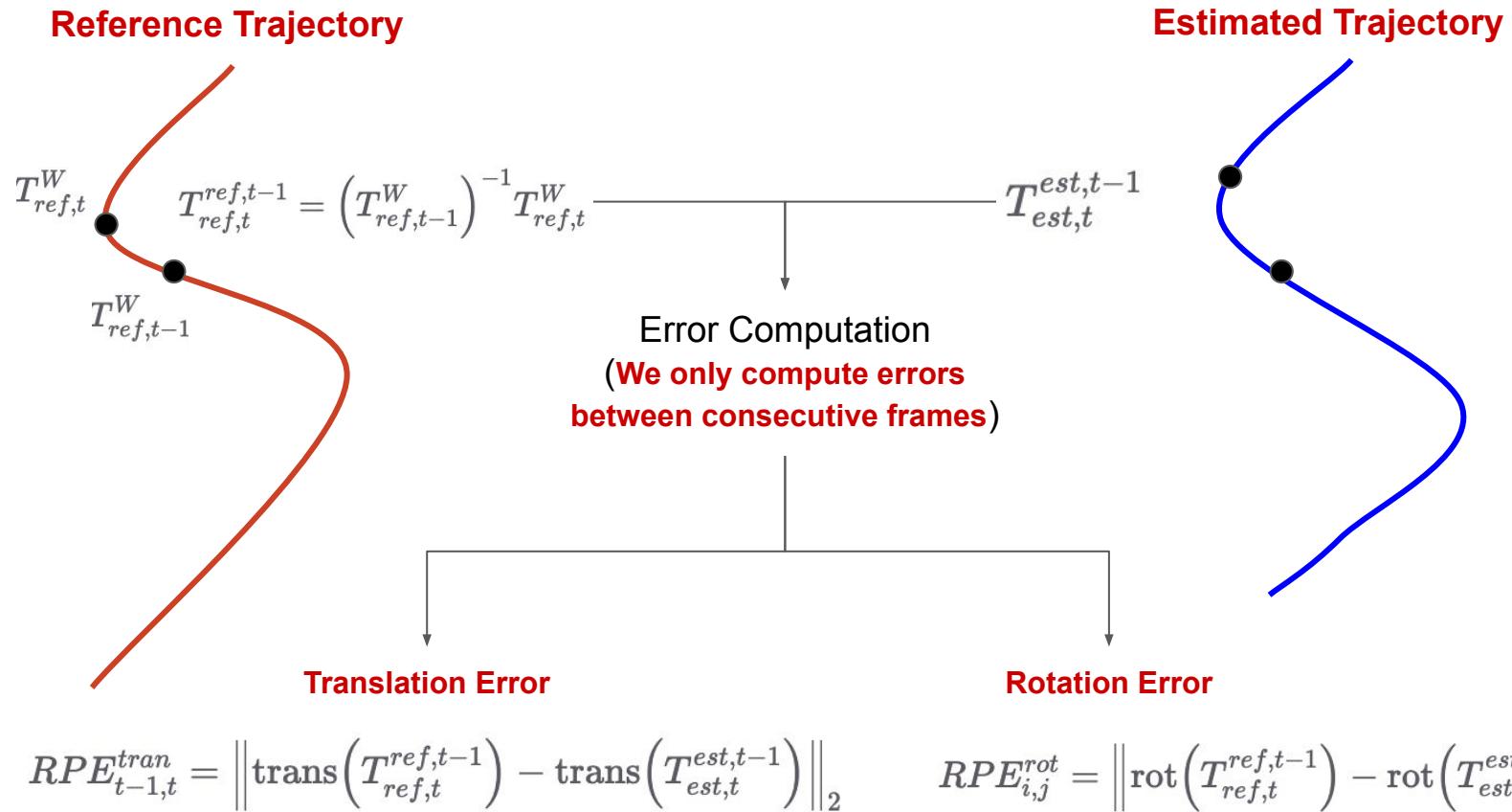
Images



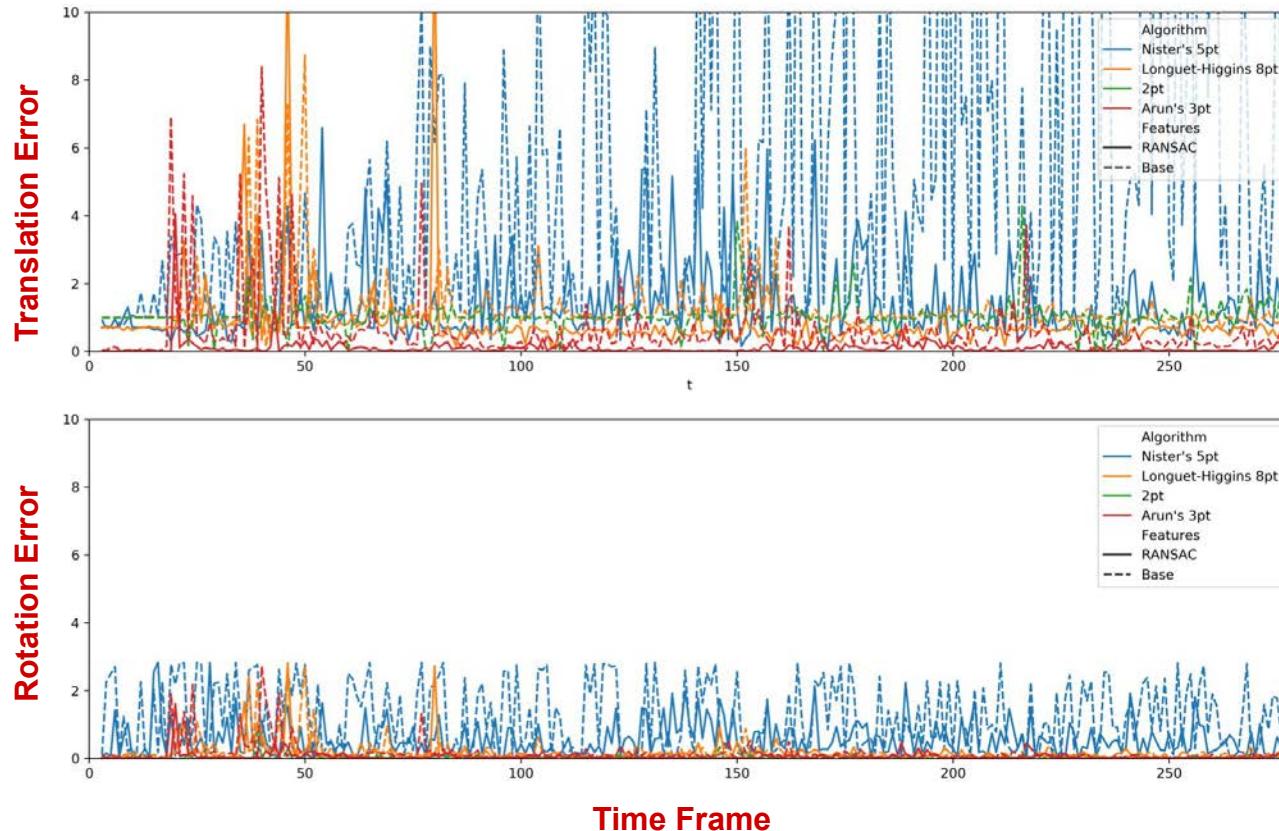
Red arrow:  
GT pose

Yellow arrow:  
Estimated pose

# Evaluate the Performance of Algorithms



# Submission: Plots of the Statistics



[https://mit-spark.github.io/VN\\_AV2020-handouts/lab6/](https://mit-spark.github.io/VN_AV2020-handouts/lab6/)

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