Flow of the data:

Main function

SLAM.GetImageScale() is called (84)
Image is read using cv::imread (99)
Image is resized using cv::resize (120)
Image is then passed to SLAM.TrackMonocular(im,tframe) where iframe is “double tframe = vTimestampsCam[seq][ni];” (140)

System

TrackMonocular (399)
Image is cloned to imToFeed (414)
GrabImageMonocular() is called where the imToFeed is sent (466)

Tracking object is created which takes _settings object (191)
_settings object is created (79) which takes the values from setting file

All the settings are in the EuRoC.yaml file

Tracking (1566)

Converting to gray scale (1568)
Object of Frame is created (1587) by sending the grayscale image
Also the ORBExtractor’s object is created in header file which happens to be a pointer along with BoW’s (ORBVocabulary) object

Orb object is created. If monocular then number of features is 5*nFeatures (601)
nFeatures is set from settings->nFeatures() (589)

Frame(289)

Frame ID is generated (296)
ORB extraction is done with the gray scale image (311)