**READ ME-Monocular Visual Odometry**

**This example provides relative SE3 transformations for first 302 poses.**

1. Download folder named Monocular Visual Odometry.
2. Run function posecalc.m.
3. Open the function Data\_Edit and change the path directory in line 20 of Data\_Edit to point towards the file named image01 within the monocular visual odometry folder.
4. Open VisualOdometryExample\_2.m and run the code.
5. Go back into the Data\_Edit.m function and change the variable “starter” in line 2 of the code to a value of 102.
6. Change the directory in line 20 of Data\_Edit to point towards the file named image02 within the monocular visual odometry folder.
7. Run the VisualOdometryExample\_2.m.
8. Go back into the Data\_Edit.m function and change the variable “starter” in line 2 of the code to a value of 202.
9. Change the directory in line 20 of Data\_Edit to point towards the file named image03 within the monocular visual odometry folder.
10. The variable Relative\_total contains the relative SE3 transformations between the first 302 poses of the trajectory. And is used in the factor graph construction.