
Activities
Terminator
二6月 22 11:15
Sensors:
GNSS QR Code Trajectory
Camera Lidar IMU Odom
Applications:
UAV Self-driving Robots AR/VR
Monocular Camera
RGB-D Camera
Stereo Camera
Cameras: Mono Stereo RGBD
No depth Passive Active
State Estimation Problem
Euler Angles
Quarternion
Rodrigues' Formula
Baker-Campbell-Hausdorff Formula:
Perturbation Model
Left/Right Jacobians
Stereo Camera
Pinhole Camera Model
Pin-hole Model
Camera Coordinates
Normal Image
Barrel-like Distortion
Cushion-like Distortion
Sim
Affine
Perspective
Newton
Gauss-Newton
Levenberg-Marquatdt
Graph Optimization
Landmarks
Camera poses
Observation model
Motion model
Trust region
Sparse BA
Arrow-like Hessian
Schur-trick
Robust kernel
Fill-in in Marginalization
Open-source SLAM
xiang@idriver-work:~
xiang@idriver-work:~ 80x24
11:14:45
apt-get
Home
Recent
Starred
Home
Desktop
Documents
Downloads
Music
Pictures
Videos
Trash
dataset
Other Locations
Code
Data
Desktop
Documents
Downloads
Music
Pictures
Public
ros
Software
Templates
Videos
桌面
marker.rviz
Feature Matching
ORB features
Brute-force Matching
Pose only BA:
2D-2D: Epipolar Geometry
Triangulation
Coarse-to-fine tracking
Layer 1
Layer 2
Image 1
Raw image
Image 2
Constant Grayscale Assumption
Bundle Adjustment
Pose Graph
Pose Graph
time
Name
Sensors
URL
MonoSLAM
PTAM
ORB-SLAM
https://github.com/hanmekim/SceneLib2
http://www.robots.ox.ac.uk/~gk/PTAM/
http://webdiis.unizar.es/~raulmur/orbslam/