Abstract:

SLAM，SLAM with Kinect

Task 1st week:

1、熟悉SLAM，属于《计算机视觉》Computer vision内容

2、安装Kinect，熟悉Kinect编程

Knowledge:

[1] about SLAM, search documents for Baidu,

<http://wenku.baidu.com/search?word=SLAM+&lm=0&od=0&fr=top_home&fr_ext=ceiling>

[2] SLAM for dummies, <http://wenku.baidu.com/view/32d390f3ed630b1c58eeb512.html>

[3] 视觉SLAM漫淡, <http://www.tuicool.com/articles/BRf6Fb>

[4] 基于RGBD的mapping, <http://www.cnblogs.com/cv-pr/p/5650636.html>

[5] Endres, Felix, et al. "3-D mapping with an RGB-D camera." IEEE Transactions on Robotics 30.1 (2014): 177-187. Source code: <https://github.com/felixendres/rgbdslam_v2>

[6] Labbé, Mathieu, and François Michaud. "Online global loop closure detection for large-scale multi-session graph-based slam." 2014 IEEE/RSJ International Conference on Intelligent Robots and Systems. IEEE, 2014. Real-Time Appearance-Based Mapping: <http://introlab.github.io/rtabmap/>