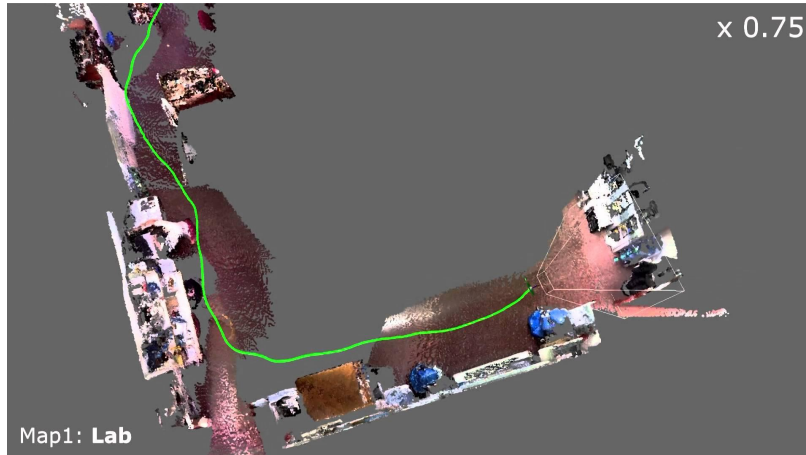




# Robust monocular visual odometry



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Tracking the ego-motion of a camera in 3D-space is an important problem that arises in many applications. We have the basic building blocks (dense image alignment, stereo, depthmap fusion), it remains to combine them into a full visual odometry system.

Goals:

- Understand the algorithms involved
- Design and implement a robust monocular odometry system