Practical Course: Vision Based Navigation

Premeeting

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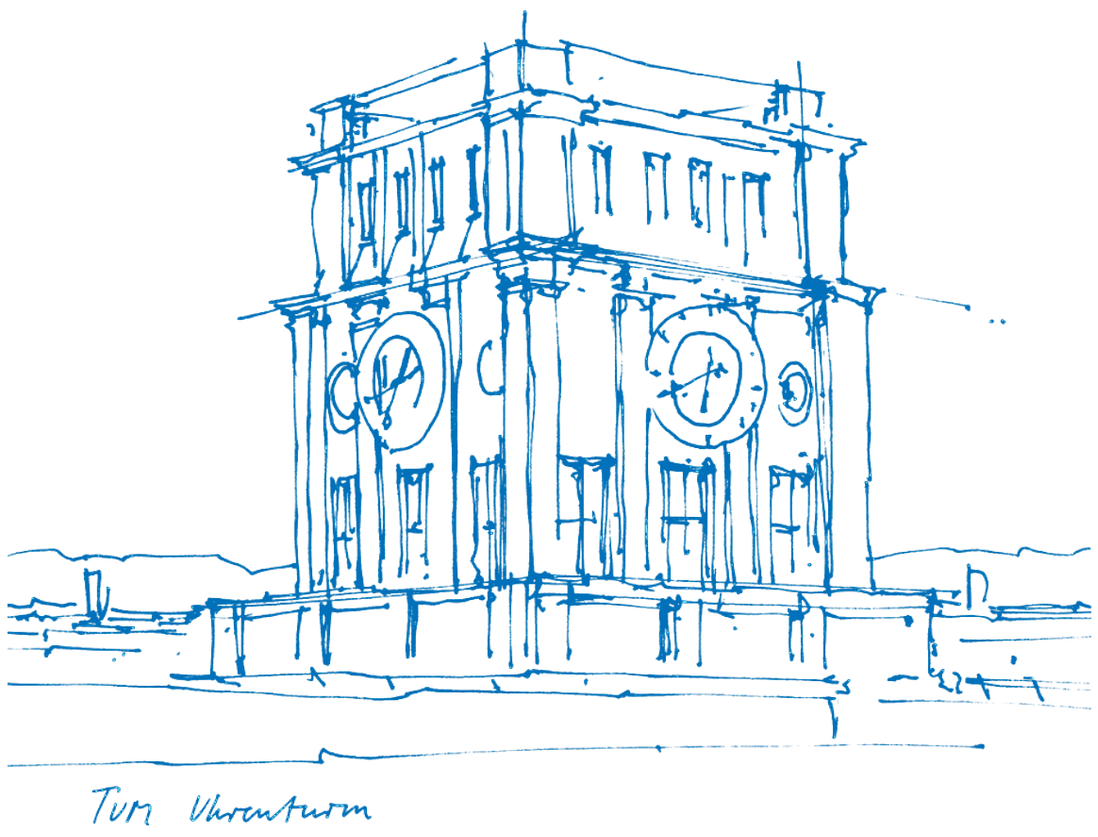
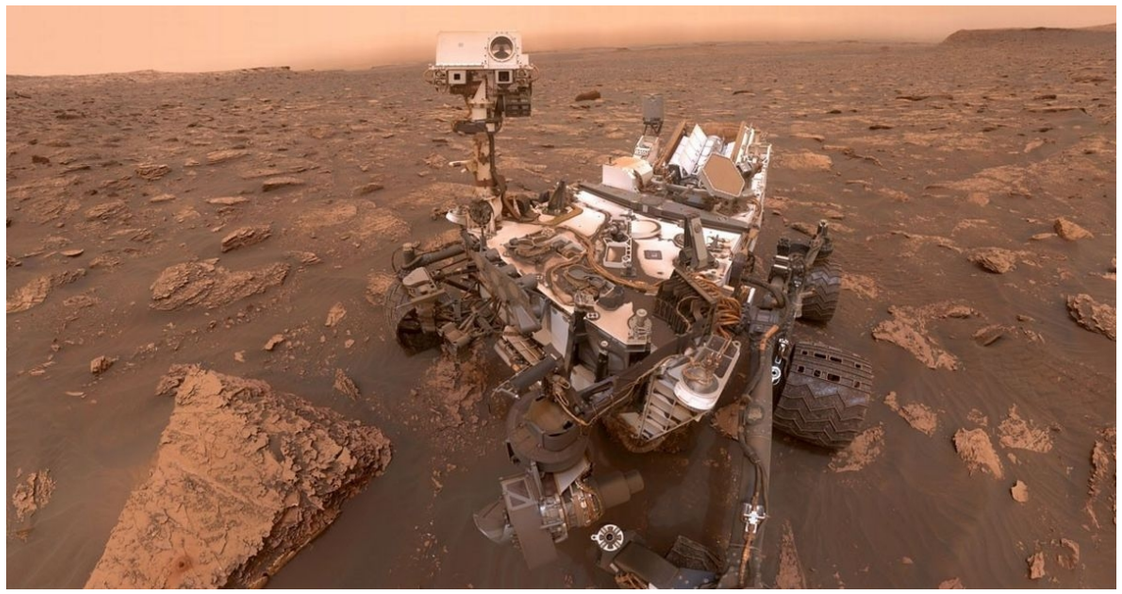
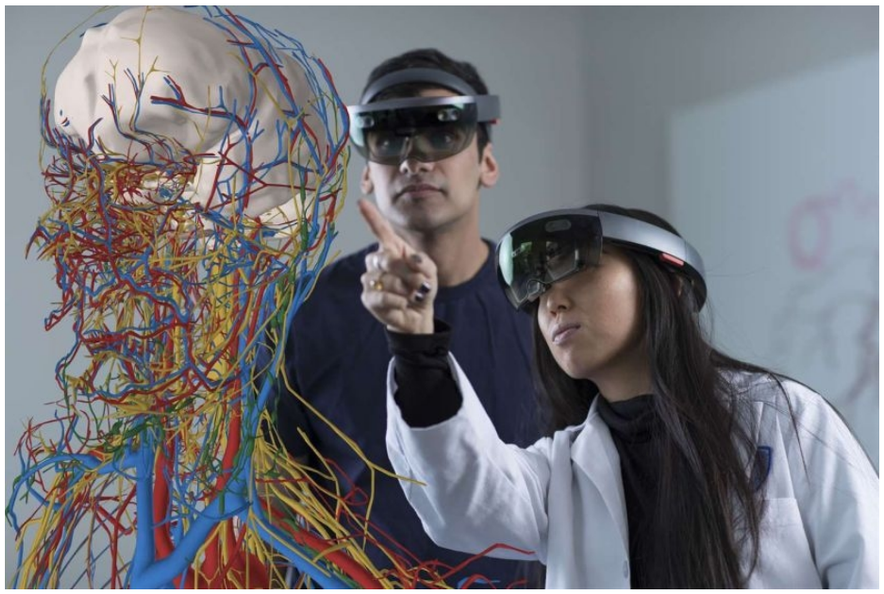


Motivations

No GPS



Pose estimation



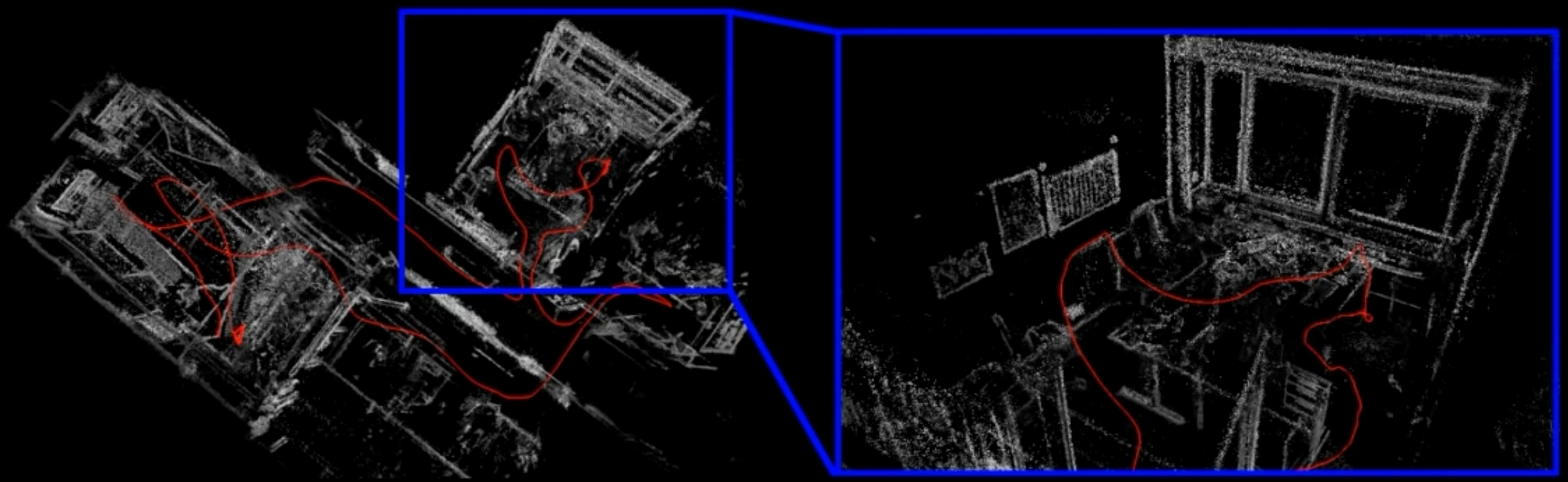
3D reconstruction

Path planning(when we have a map)

Direct Sparse Odometry

Jakob Engel[1,2], Vladlen Koltun[2], Daniel Cremers[1]

July 2016



[1]Computer Vision Group
Technical University Munich

[2]Intel Labs

ORB-SLAM

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Content of this course

- You will gain practical experience with
  - Visual odometry and localisation / state estimation
  - Vision-based Simultaneous Localization and Mapping (SLAM)
  - Structure from Motion (SfM)

- Implementation of algorithms

- Benefits / drawbacks of specific methods when applied to concrete, relevant problems

- Get familiar with relevant software libraries (Eigen, Ceres, OpenGV, …)

- Learn how to work in teams / on projects

- Improve your presentation skills

Course organisation

- Course takes place during the lecture period

- The course will be held in person
  - Work on your own Linux desktop / laptop

Course organisation

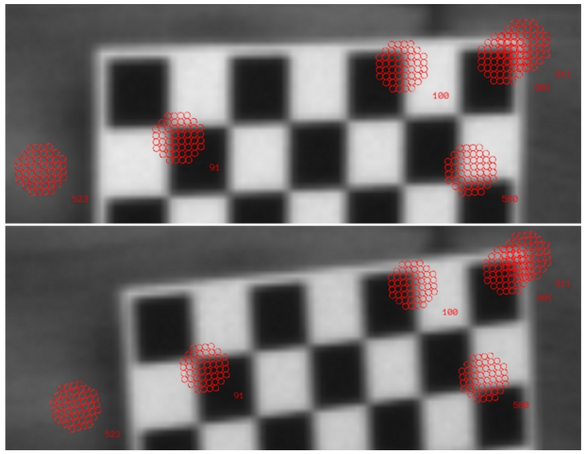
- Initial phase (first 5 weeks): Lectures & Exercises
  - Wednesdays 2-4 pm lecture
  - Wednesdays 4-6 pm exercise session
  - Programming assignments will be handed out every week and checked / graded by the tutors
  - Assignments are worked on individually by every student; each participant should be able to explain their solution
  - Attendance to lecture and exercise sessions voluntary (but **highly** encouraged)

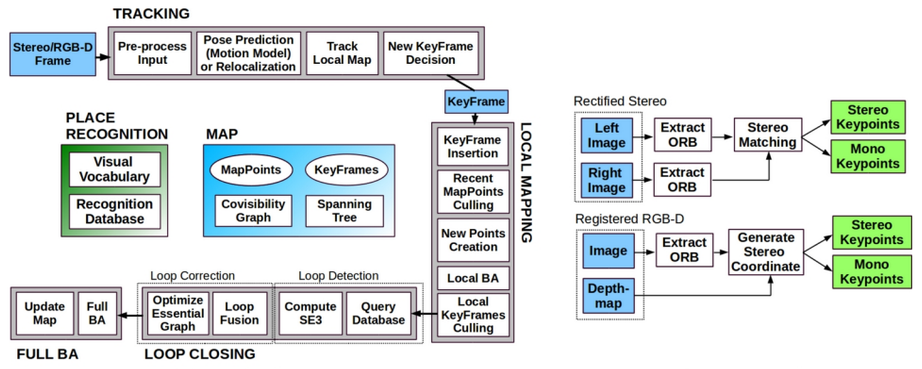
Course organisation

- Second phase (6 weeks): project
  - Work in small groups (1-2 people) on a project
  - Mandatory weekly meeting with tutors to discuss progress and next steps (Mondays 2-6 pm)
  - Implement a specific algorithm / extension / paper, which one tbd
  - Present project outcome in talk and Q&A session (15 mins per group + 5 mins Q&A)
  - Written report on project outcome (10-12 pages, single column, single-spaced lines, 11pt)

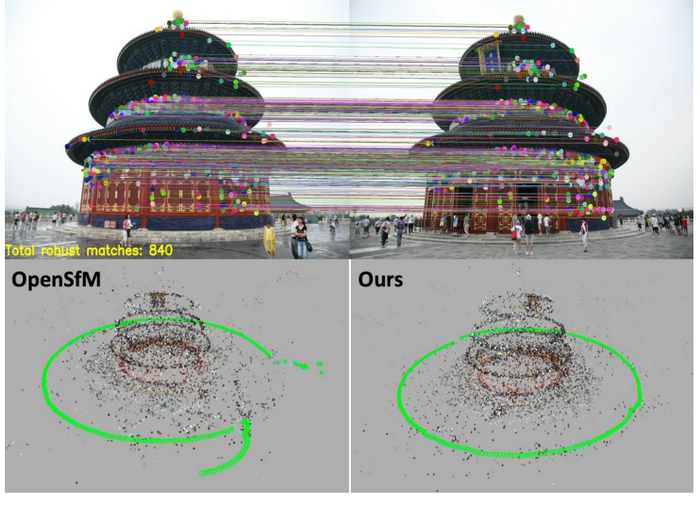
Topics covered

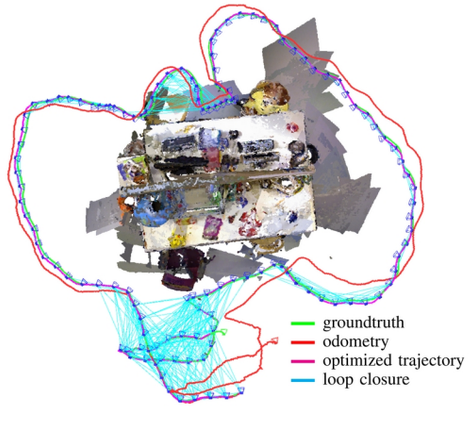
- 3D geometry and camera models
- Non-linear optimisation and camera calibration
- Feature detectors and descriptors, feature matching, RANSAC
- Offline Structure from Motion, Bundle Adjustment
- Visual odometry and SLAM (online BA)
- Possible topics for projects:
  - Large-scale consistency for SLAM
  - Visual place recognition
  - Optical flow for visual odometry
  - Direct methods (odometry, BA)
  - Dense reconstruction
  - Rotation / Translation averaging (global SfM)
  - …

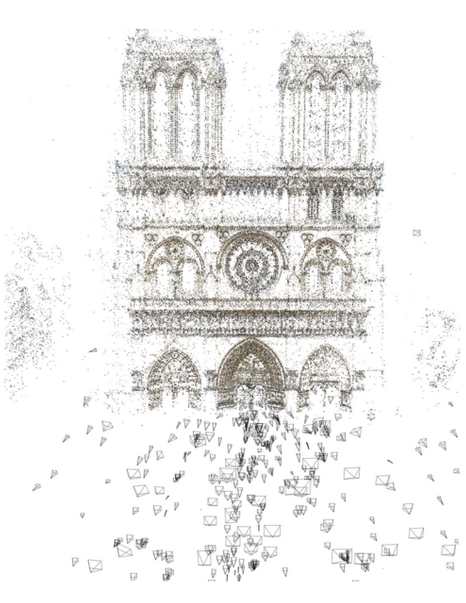


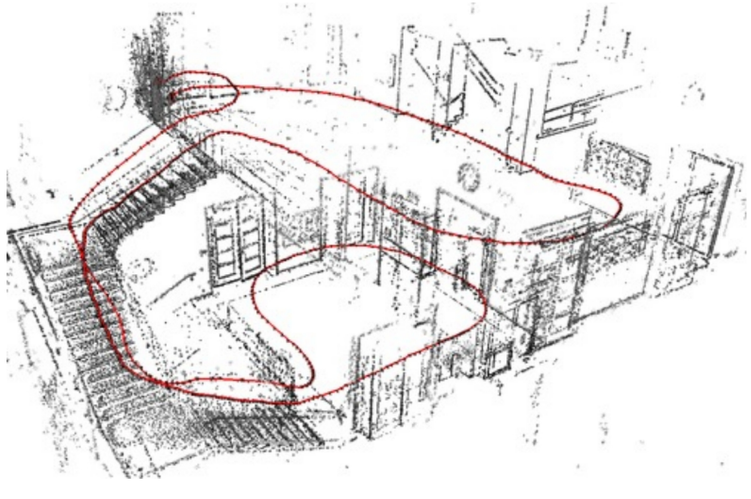


(a) System Threads and Modules. (b) Input pre-processing









Course requirements

- **Good knowledge of the C/C++ language is essential**
- Good knowledge of basic mathematics such as linear algebra, calculus, probability theory, and numerics is required
- Prior practical knowledge in robotics and computer vision topics is a plus
- Participation in the **Computer Vision II: Multiple View Geometry**
  - Similar lectures can also be accepted

Course registration

- Apply for this course through the matching system: https://matching.in.tum.de/

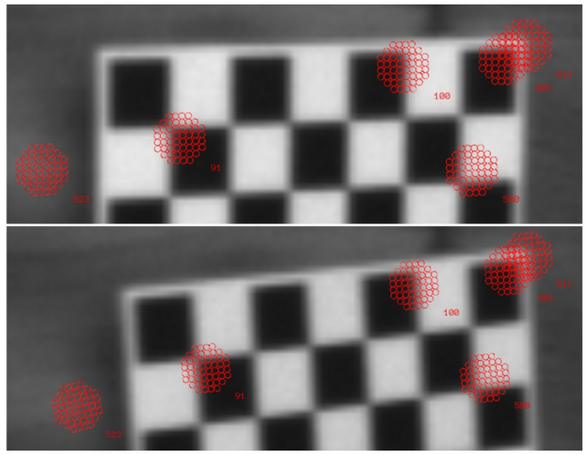
- Additionally, you send us an email:
  - Please specify how you meet the course requirements / if you have attended any related computer vision courses before!
  - **Comment on you programming experience in C++!** (e.g. List concrete examples of projects you have worked on.)
  - Send all your grade transcripts, in particular showing any lectures on pre-requisite topics (computer vision / robotics / maths) that you have attended to:
    visnav-ss24@vision.in.tum.de

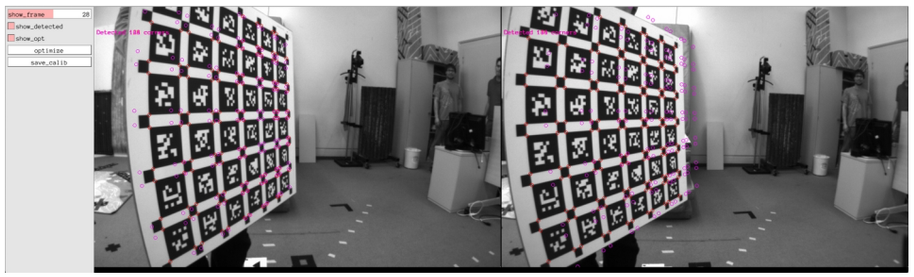
- The deadline for the matching system and prerequisite email is 14.02.2023.

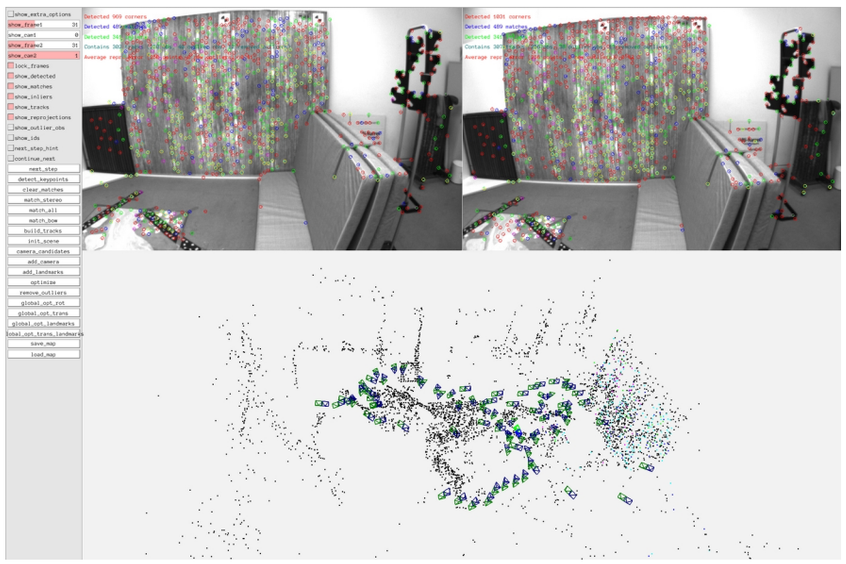
- We can only guarantee places to students assigned through the matching process (and fitting the course requirements)!

- Watch announcements on the course website:
  https://cvg.cit.tum.de/teaching/ss2024/visnav_ss2024

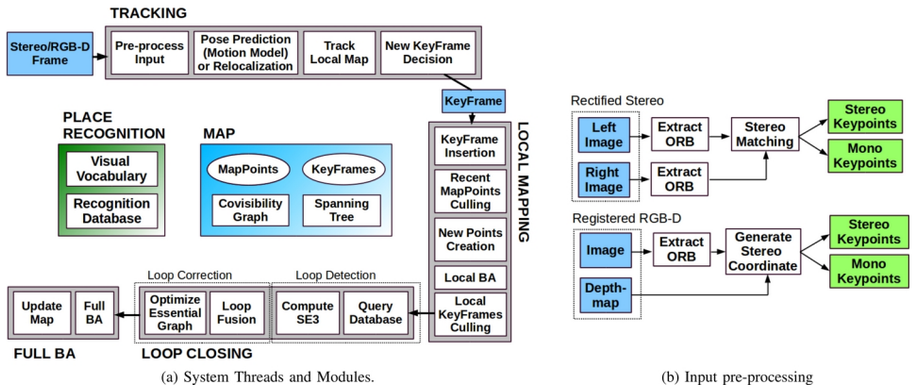
- The course starts on Wednesday, 17.04.2023







Questions?



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