

# Keyframe based SLAM



Team Pixel

# Approach

- Feature detection with BRISK
- Select Keyframes according to some selection criteria
  - Every 25 frames
  - Distance threshold
- Compute pose from 3D-to-2D matches
- Optionally: Do Bundle Adjustment with Ceres-solver/  
GTO

# Goals

- Reduce drift considerably
- Run in real-time
- Optionally: Recover from tracking loss
- Optionally: Using global map consistency

# Discussion

