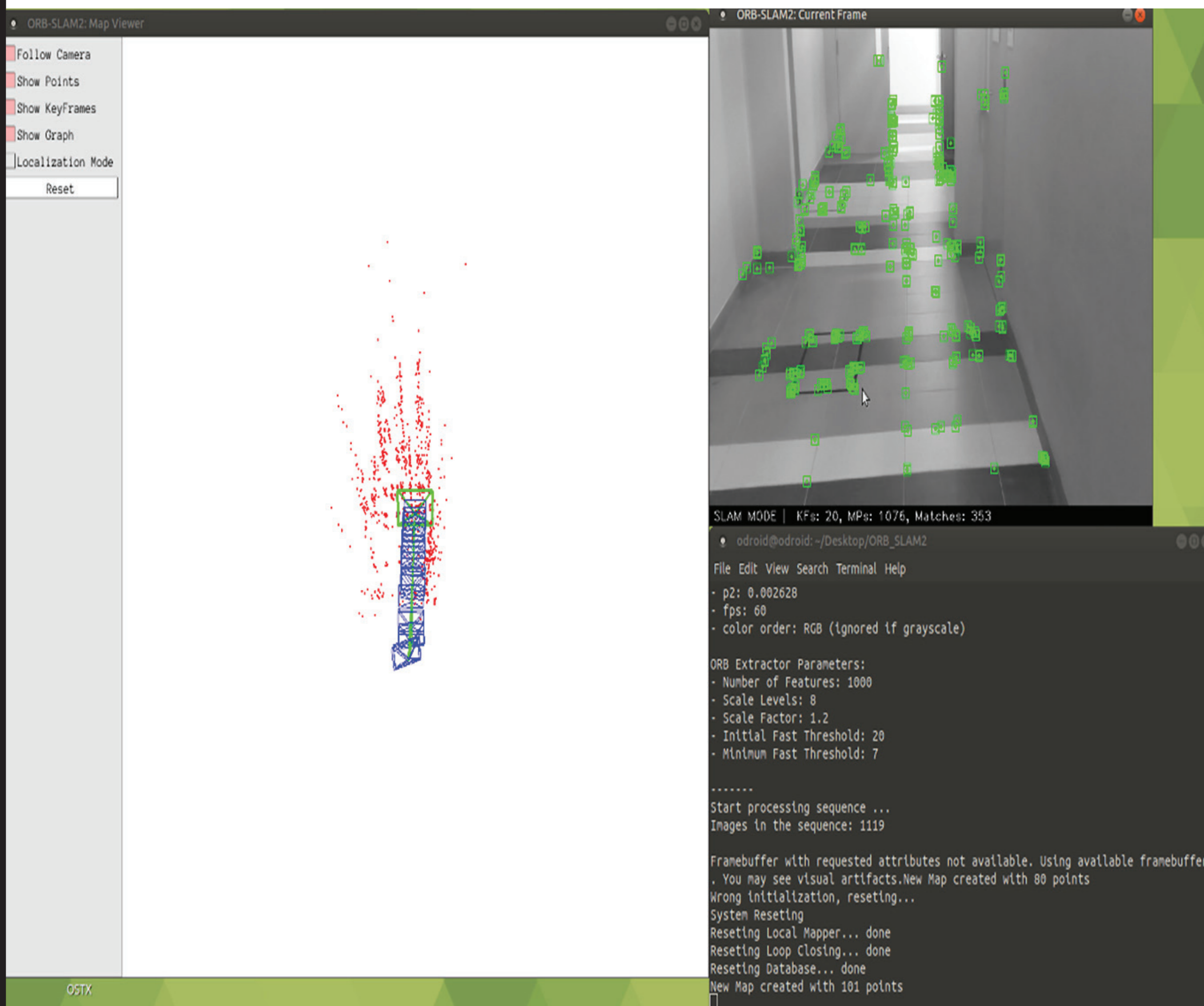


Real-Time Visual SLAM on Embedded Platforms

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Project objectives:

This project aims to improve the robustness of a popular visual localisation algorithm, ORB-SLAM2. ORB-SLAM2 utilises Oriented fast and Rotated Brief to select points (pixels) in images to track movements of the camera. As selected points could lie on dynamic objects (such as people), this could cause incorrect tracking. Semantic segmentation is applied on frames to identify possible dynamic objects and an efficient algorithm will be implemented to remove points (pixels) on the dynamic objects to improve the tracking accuracy.