The KITTI Vision Benchmark Suite

A project of Karlsruhe Institute of Technology and Toyota Technological Institute at Chicago

Karlsruhe Institute of Technology

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Visual Odometry / SLAM Evaluation 2012

The odometry benchmark consists of 22 stereo sequences, saved in loss less png format: We provide 11 sequences (00-10) with ground truth trajectories for training and 11 sequences (11-21) without ground truth for evaluation. For this benchmark you may provide results using monocular or stereo visual odometry, laser-based SLAM or algorithms that combine visual and LIDAR information. The only restriction we impose is that your method is fully automatic (e.g., no manual loop-closure tagging is allowed) and that the same parameter set is used for all sequences. A development kit provides details about the data format.

- Download odometry data set (grayscale, 22 GB)
- Download odometry data set (color, 65 GB)
- Download odometry data set (velodyne laser data, 80 GB)
- Download odometry data set (calibration files, 1 MB)
- Download odometry ground truth poses (4 MB)
- Download odometry development kit (1 MB)
- Lee Clement and his group (University of Toronto) have written some python tools for loading and parsing the KITTI raw and odometry datasets

Kitti Benchmark Dataset For Visual Odometry Slam Cvlibs

Andrey Ronzhin,Gerhard Rigoll,Roman Meshcheryakov

Kitti Benchmark Dataset For Visual Odometry Slam Cvlibs:

Recent Advances in Computer Vision Mahmoud Hassaballah,Khalid M. Hosny,2018-12-14 This book presents a collection of high quality research by leading experts in computer vision and its applications Each of the 16 chapters can be read independently and discusses the principles of a specific topic reviews up to date techniques presents outcomes and highlights the challenges and future directions As such the book explores the latest trends in fashion creative processes facial features detection visual odometry transfer learning face recognition feature description plankton and scene classification video face alignment video searching and object segmentation It is intended for postgraduate students researchers scholars and developers who are interested in computer vision and connected research disciplines and is also suitable for senior undergraduate students who are taking advanced courses in related topics However it is also provides a valuable reference resource for practitioners from industry who want to keep abreast of recent developments in this dynamic exciting and profitable research field **Methods for Appearance-based Loop Closure Detection** Emilio Garcia-Fidalgo,Alberto Ortiz,2018-03-14 Mapping and localization are two essential tasks in autonomous mobile robotics Due to the unavoidable noise that sensors present mapping algorithms usually rely on loop closure detection techniques which entail the correct identification of previously seen places to reduce the uncertainty of the resulting maps This book deals with the problem of generating topological maps of the environment using efficient appearance based loop closure detection techniques Since the quality of a visual loop closure detection algorithm is related to the image description method and its ability to index previously seen images several methods for loop closure detection adopting different approaches are developed and assessed Then these methods are used in three novel topological mapping algorithms The results obtained indicate that the solutions proposed attain a better performance than several state of the art approaches To conclude given that loop closure detection is also a key component in other research areas a multi threaded image mosaicing algorithm is proposed This approach makes use of one of the loop closure detection techniques previously introduced in order to find overlapping pairs between images and finally obtain seamless mosaics of different environments in a reasonable amount of time Interactive Collaborative Robotics Andrey Ronzhin,Gerhard Rigoll,Roman Meshcheryakov,2018-09-10 This book constitutes the proceedings of the Third International Conference on Interactive Collaborative Robotics ICR 2018 held in Leipzig Germany in September 2018 as a satellite event of the 20th International Conference on Speech and Computer SPECOM 2018 The 30 papers presented in this volume were carefully reviewed and selected from 51 submissions The papers presents challenges of human robot interaction robot control and behavior in social robotics and collaborative robotics as well as applied robotic and cyberphysical systems *Computer Vision – ECCV 2022 Workshops* Leonid Karlinsky,Tomer Michaeli,Ko Nishino,2023-02-11 The 8 volume set comprising the LNCS books 13801 until 13809 constitutes the refereed proceedings of 38 out of the 60 workshops held at the 17th European Conference on Computer Vision ECCV 2022 The conference took place

in Tel Aviv Israel during October 23 27 2022 the workshops were held hybrid or online The 367 full papers included in this volume set were carefully reviewed and selected for inclusion in the ECCV 2022 workshop proceedings They were organized in individual parts as follows Part I W01 AI for Space W02 Vision for Art W03 Adversarial Robustness in the Real World W04 Autonomous Vehicle Vision Part II W05 Learning With Limited and Imperfect Data W06 Advances in Image Manipulation Part III W07 Medical Computer Vision W08 Computer Vision for Metaverse W09 Self Supervised Learning What Is Next Part IV W10 Self Supervised Learning for Next Generation Industry LevelAutonomous Driving W11 ISIC Skin Image Analysis W12 Cross Modal Human Robot Interaction W13 Text in Everything W14 BioImage Computing W15 Visual Object Oriented Learning Meets Interaction Discovery Representations and Applications W16 AI for Creative Video Editing and Understanding W17 Visual Inductive Priors for Data Efficient Deep Learning W18 Mobile Intelligent Photography and Imaging Part V W19 People Analysis From Face Body and Fashion to 3D Virtual Avatars W20 Safe Artificial Intelligence for Automated Driving W21 Real World Surveillance Applications and Challenges W22 Affective Behavior Analysis In the Wild Part VI W23 Visual Perception for Navigation in Human Environments The JackRabbot Human Body Pose Dataset and Benchmark W24 Distributed Smart Cameras W25 Causality in Vision W26 In Vehicle Sensing and Monitorization W27 Assistive Computer Vision and Robotics W28 Computational Aspectsof Deep Learning Part VII W29 Computer Vision for Civil and Infrastructure Engineering W30 AI Enabled Medical Image Analysis Digital Pathology and Radiology COVID19 W31 Compositional and Multimodal Perception Part VIII W32 Uncertainty Quantification for Computer Vision W33 Recovering 6D Object Pose W34 Drawings and Abstract Imagery Representation and Analysis W35 Sign Language Understanding W36 A Challenge for Out of Distribution Generalization in Computer Vision W37 Vision With Biased or Scarce Data W38 Visual Object Tracking Challenge

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