Abstract

SLAM algorithm is very important in the process of building maps for robots, the speed of building maps affects much from algorithms, hardware speed, image resolution. The integration on raspberry pi increases the flexibility of building a robot model, but the speed of raspberry pi is not high, so we propose a method of speeding up by building a vector model for the D435i camera and accelerating process on usb intel modivus.

References


Index Terms

Computer Science  Algorithms

Keywords
SLAM, Modivus, D435i, LMedS