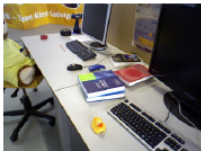# Robust Odometry Estimation for RGB-D Cameras
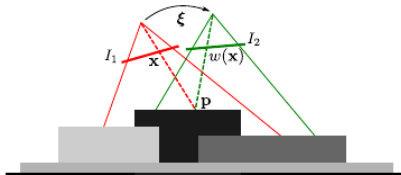Kerl, Sturm, Cremers; ICRA 2013

(a) reference image I_1 (b) current image I_2

Problem: Given two consecutive images I_1 and I_2, find relative pose ξ.

Given:
- Real-time CPU implementation
- Paper

- Hands-on with Kinect

Goals:
- Refactor to real-time (or even faster)
- Estimate ξ by minimizing photometric and geometric error
- Implement different weightings: Huber, Student-t, Cauchy
- Implement iteratively re-weighted least squares

Supervisor: Bjoern