Frame-to-frame feature-based ego-motion estimation using stereo cameras

Current approach: Rotation and translation of the ego-motion in two separate processes

An analysis of the characteristics of the optical flows and reprojection errors that are independently induced by each of the decoupled six degrees of freedom motion

A reprojection error that depends on the coordinates of the features

Decoupling the translation flow from the overall flow
  - Using an initial rotation estimate
  - Transforming the correspondences into a pure translation scenario

Evaluated on KITTI, the best translation error of all camera-based methods