Real-Time Monocular Visual Odometry for On-Road Vehicles with 1-Point RANSAC

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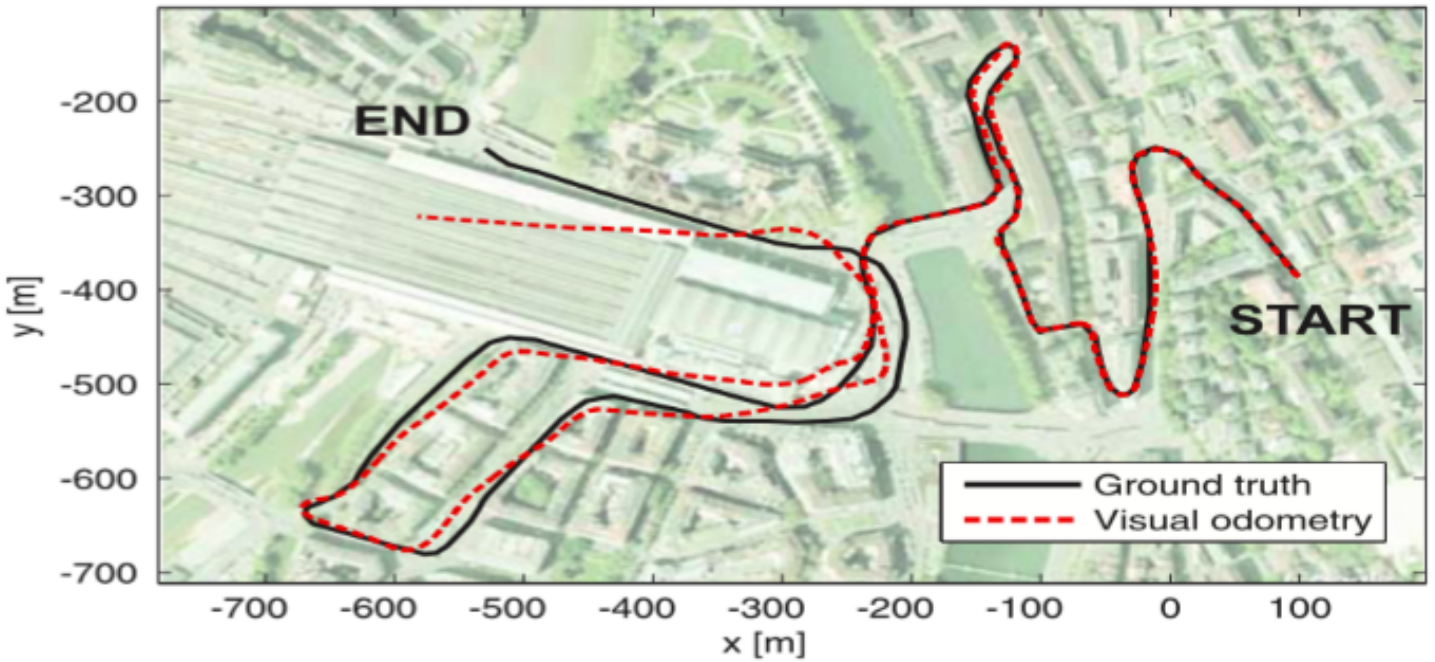

- Presents a system capable of recovering the trajectory of a vehicle from the video input of a single camera at a very high frame-rate
- Contributions:
  - The algorithm proposes a novel way of removing the outliers of the feature matching process
  - Show that by exploiting the nonholonomic constraints of wheeled vehicles it is possible to use a restrictive motion model
  - This allows to parameterize the motion with only 1 feature correspondence
- Evaluates on real traffic sequencees in the city center of Zurich