

Progress Update (2/24/16)

Juan Vazquez

The combined Ethernet detection and classification program is now able to run continuously while capturing and storing data packets from the VLP-16. However, the program execution is slower than desired and currently only captures six packets for each full 360 degree rotation. Data is currently saved and read from text files and I've begun to replace this technique by implementing the use of arrays.

David Bumpus

After extracting keypoints from the 3D point cloud and 2D image, I began researching a method for compressing the 3D point cloud into 2D for feature detection. I have explored the use of a range image. I am currently using range images to register the point cloud and image. I will continue to work at the same pace.

Daniel Kubik

This week I have successfully converted a .ppm image to a two-dimensional PCL point cloud. Keypoint detection did not return useful results on this point cloud, so I will continue looking into ways to represent 3D data in a 2D image. I will continue working at the same pace.