Exercise: Odometry Calibration

Implement an odometry calibration tool based on a least-squares method as presented in the lecture. To support this task, we provide a small Octave framework (see course website). The framework contains the following folders:

- **data** contains the recorded raw odometry and the motion estimated by a scan-matcher for each time step.
- **octave** contains the Octave framework with stubs to complete.
- **plots** this folder is used to store images.

The below mentioned tasks should be implemented inside the framework in the directory *octave* by completing the stubs:

- Implement the functions in *ls_calibrate_odometry.m* for constructing and solving the least-squares system.
- Implement the function in *apply_odometry_correction.m* for applying the calibration matrix to a set of odometry measurements.
- Implement the function in *compute_trajectory.m* for chaining up the affine transformation matrices of the relative odometry measurements.

After implementing the missing parts, you can run the framework. To do that, change into the directory *octave* and launch *Octave*. To start the main loop, type *LSCalibrateOdometry*. The script will produce a plot showing the trajectory of the raw odometry measurements, the estimate obtained by scan-matching, and the odometry after applying the calibration. This plot will be saved in the *plots* directory. Figure 1 shows the result that you should obtain.
Some implementation tips:

- The functions `v2t` and `t2v` are available within the framework and allow to convert between a vector representing the pose of a robot and its corresponding affine transformation matrix.

- The function `reshape` returns a matrix with specified dimensions whose elements are taken from another matrix. It can, for example, convert a vector into a matrix.

- Many of the functions in Octave can handle matrices and compute values along the rows or columns of a matrix. Some useful functions that support this are `sum`, `log`, `sqrt`, `sin`, `cos`, and many others.