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THESIS

Your Name, First Lieutenant, USAF

AFIT-ENG-MS-20-90210

**DEPARTMENT OF THE AIR FORCE
AIR UNIVERSITY**

AIR FORCE INSTITUTE OF TECHNOLOGY

Wright-Patterson Air Force Base, Ohio

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THESIS

Presented to the Faculty
Department of Electrical and Computer Engineering
Graduate School of Engineering and Management
Air Force Institute of Technology
Air University
Air Education and Training Command
in Partial Fulfillment of the Requirements for the
Degree of Master of Science in Electrical Engineering

Your Name, B.S.E.E.

First Lieutenant, USAF

March 26, 2020

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THESIS

Your Name, B.S.E.E.
First Lieutenant, USAF

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Your Advisor, Ph.D
Chair

First Committee Member, Ph.D
Member

Second Committee Member, Ph.D
Member

Abstract

Cool, awesome abstract that tells people why they should read your awesome thesis.

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I. Introduction

Overview the chapter here

1.1 First Section Title Here

Modern navigation solutions used in practical applications substantially rely on the use of the Global Positioning System (GPS), as when fully operational, no other technology can currently achieve a similar performance. Blah...

1.1.1 Classical Cameras and Feature Detection

1.2 Research Objectives

The primary goal of this research is to ...

1.3 Document Overview

This document is organized as follows. Chapter II provides an overview of relevant background information. Chapter III details the process of training a Convolutional Neural Network (CNN) that produces feature points and descriptors, and the method of evaluating this network. Chapter IV presents the results of evaluating variations of the feature detector/descriptor network, as well as the results of the Event Visual-inertial Odometry (EVIO) pipeline. Finally, Chapter V discusses the conclusions drawn from the results.

1.4 First Section Title Here

Text description here, can reference other Chapters or Sections, like Chapter I or ??.

1.4.1 Subsection Title Here

Take about an equation with text without space, like

$$\frac{1}{z} \begin{bmatrix} u \\ v \\ 1 \end{bmatrix} = K \begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} f_x & 0 & c_x \\ 0 & f_y & c_y \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \end{bmatrix} \quad (1)$$

where λ can be referenced. Don't put lines before or after equations, unless the equation is the end of a paragraph's discussion.

You can also include an algorithm, like Algorithm 1.

Reference equations a little differently like (1). Or reference a table like Table 1.

Algorithm 1 Algorithm Title Here

```
1: function FOO( $a, b, c$ )
2:    $\mathbf{R}_W^{C_0}, \mathbf{p}_{C_0}^W \leftarrow \text{GETPOSE}(e_0.t)$  ▷ Target pose
3:   for  $k \leftarrow 1, N$  do ▷ Loop over events
4:      $\begin{bmatrix} x_H \\ y_H \end{bmatrix} \leftarrow \text{UNDISTPOS}(e_x, e_y)$  ▷ Pixel location to position
5:   end for
6:   return  $image$  ▷ Output
7: end function
```

Table 1: Table Title Here

Description	Variable	Value
Focal lengths	f_x	198.444
	f_y	198.826
Image Center	c_x	104.829
	c_y	92.838
Radial Distortion	k_1	-0.394
	k_2	0.156
	k_3	0
Tangential Distortion	p_1	-0.125×10^{-3}
	p_2	-1.629×10^{-3}

II. Background and Literature Review

Overview the chapter here

2.1 Visual Odometry

Add descriptions, figures, cool text and more to this chapter! For example:

And cite cool literature, like this [1].

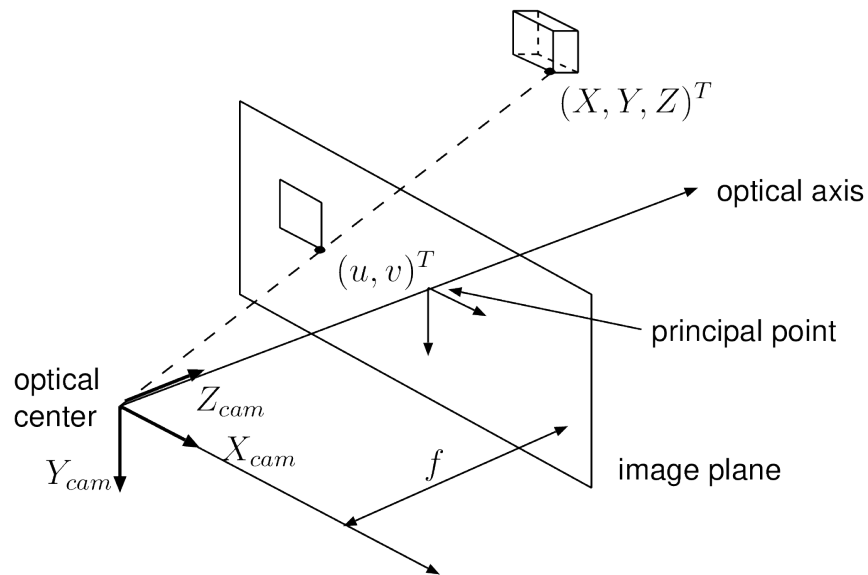


Figure 1: Longer, more descriptive caption for under the figure. This caption should stand alone (with the image of course). For example: Perspective Projection Pinhole Camera Model: 3-D objects in space are projected through an optical center onto a 2-D image plane.

III. Methodology

Preamble

The methodology described in this chapter is inspired by a combination of research to build an Event Visual-inertial Odometry (EVIO) pipeline....

3.1 Programming Platform

The Python programming language [?] was used with multiple specialized libraries throughout this work mainly for its compatibility with the TensorFlow ...

3.1.1 Some Cool Equations

First, prior to propagating the covariance as described in ??, Φ_k is modified according to Equation (2) - Equation (4), where Φ_{11} , Φ_{31} and Φ_{51} correspond to the first, third and fifth 3×3 blocks in the first three columns of Φ_k .

$$\Phi_{11} = \mathbf{R}_{I,k|k-1}^{I,k+1|k} = \mathbf{R}_G^{I,k+1|k} \mathbf{R}_{I,k|k-1}^G \quad (2)$$

$$\Phi_{31} \mathbf{R}_{G,k|k-1}^I \mathbf{g}^G = ([\hat{\mathbf{v}}_{I,k|k-1}^G \times] - [\hat{\mathbf{v}}_{I,k+1|k}^G \times]) \mathbf{g}^G \quad (3)$$

$$\Phi_{51} \mathbf{R}_{G,k|k-1}^I \mathbf{g}^G = (\delta t [\hat{\mathbf{v}}_{I,k|k-1}^G \times] - [\hat{\mathbf{p}}_{I,k+1|k}^G \times]) \mathbf{g}^G \quad (4)$$

IV. Results and Analysis

Preamble

Fill this with your cool results

4.1 Awesome Stuff I got to Work

V. Conclusions

In this thesis we did cool stuff...

5.1 Future Work

Stuff you would have been able to accomplish if you had been able to clone yourself.

- Saved all stranded kittens everywhere
- World Peace
- 5 incredible, completely true bullets for my TR.

Add some heavy derivations, extra data and/or plots here.

Bibliography

1. Davide Scaramuzza and Friedrich Fraundorfer. Visual odometry part I: The first 30 years and fundamentals. *Robotics and Automation Magazine*, pages 80—92, Dec 2011.

Acronyms

CNN Convolutional Neural Network. 1

EVIO Event Visual-inertial Odometry. 1, 5

GPS Global Positioning System. 1

REPORT DOCUMENTATION PAGE

Form Approved
OMB No. 0704-0188

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1. REPORT DATE (DD-MM-YYYY) 26-03-2020		2. REPORT TYPE Master's Thesis		3. DATES COVERED (From — To) Sept 2018 — Mar 2020	
4. TITLE AND SUBTITLE Hugely Specific Title That Goes Across Two Lines				5a. CONTRACT NUMBER	
				5b. GRANT NUMBER	
				5c. PROGRAM ELEMENT NUMBER	
				5d. PROJECT NUMBER	
				5e. TASK NUMBER	
6. AUTHOR(S) Name, Your, 1st Lt, USAF				5f. WORK UNIT NUMBER	
7. PERFORMING ORGANIZATION NAME(S) AND ADDRESS(ES) Air Force Institute of Technology Graduate School of Engineering and Management (AFIT/EN) 2950 Hobson Way WPAFB OH 45433-7765				8. PERFORMING ORGANIZATION REPORT NUMBER AFIT-ENG-MS-20-90210	
9. SPONSORING / MONITORING AGENCY NAME(S) AND ADDRESS(ES)				10. SPONSOR/MONITOR'S ACRONYM(S)	
				11. SPONSOR/MONITOR'S REPORT NUMBER(S)	
12. DISTRIBUTION / AVAILABILITY STATEMENT DISTRIBUTION STATEMENT A: APPROVED FOR PUBLIC RELEASE; DISTRIBUTION UNLIMITED.					
13. SUPPLEMENTARY NOTES					
14. ABSTRACT Summarized version of your awesome abstract.					
15. SUBJECT TERMS artificial neural network (ANN), convolutional neural network (CNN), deep learning, dynamic vision sensor (DVS), event-based cameras, event-based visual-inertial odometry (EVIO), Extended Kalman Filter (EKF), machine learning, multi-state constraint Kalman filter (MSCKF), neuromorphic engineering, visual odometry (VO)					
16. SECURITY CLASSIFICATION OF:			17. LIMITATION OF ABSTRACT	18. NUMBER OF PAGES	19a. NAME OF RESPONSIBLE PERSON
a. REPORT	b. ABSTRACT	c. THIS PAGE			Dr. Your Advisor, AFIT/ENG
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