



Gustavo Stefanini

ADVANCED MATERIALS AND
ROBOTICS RESEARCH CENTER

ROBOT POSE TRACKING WITH UNKNOWN FEATURE ASSOCIATION IN INDOOR ENVIRONMENTS

Matteo Unetti

22nd May 2009, h 10:00 AM

Gustavo Stefanini Center, Conference Room

La Spezia

The presentation will provide an overview of the EKF Localization algorithm with unknown correspondences implemented at CGS.

The algorithm is used to improve the localization precision of a mobile robot in a given map, using laser scanner.

The effectiveness of the procedure is demonstrated through a number of experiments, clearly showing the robustness of the method.

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