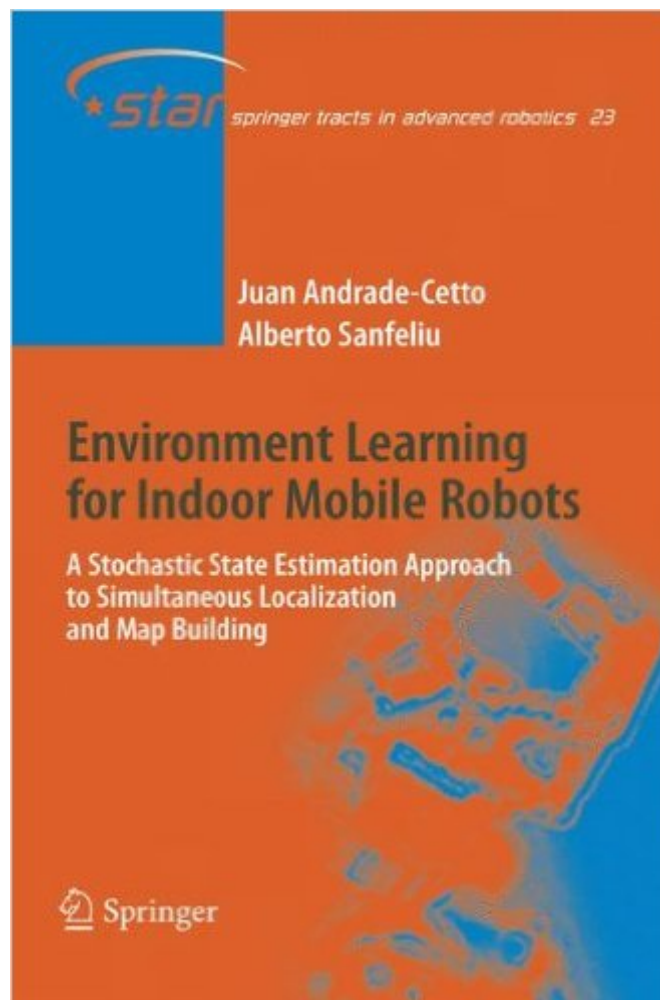


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Environment Learning For Indoor Mobile Robots: A Stochastic State Estimation Approach To Simultaneous Localization And Map Building (Springer Tracts In Advanced Robotics)





Synopsis

This monograph covers theoretical aspects of simultaneous localization and map building for mobile robots. These include estimation stability, nonlinear models for the propagation of uncertainties, temporal landmark compatibility, as well as issues pertaining the coupling of control and SLAM. One of the most relevant topics covered in this monograph is the theoretical formalism of partial observability in SLAM.

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