Robot Mapping

Course Information

Gian Diego Tipaldi, Wolfram Burgard
Topics

- Simultaneous Localization and Mapping
- Kalman filter, EKF, UKF
- Information filter
- Particle filter
- Graph-based approaches
- Least squares error minimization
- Robust optimization approaches
- Hierarchical approaches
- Data association
- SLAM front-ends
- Appearance-based approaches
- Long term operation
- Semantic mapping
Sprit of the Course

Mixture of

- Introduction to robot mapping & SLAM
- Key milestones of the past 20 years
- Relevant state-of-the-art approaches for robot mapping
- Hands on the problems – practical work
Prerequisites

- Basic math skills (LA, probabilistic concepts)
- Basic programming skills
- Useful: having attended the Introduction to Mobile Robotics course

Exam

- Oral exam
Who Attended Introduction to Mobile Robotics?
Lecture and Exercise

- Lecture: Mondays 16-18
- Exercise: Thursdays 16-18
- 22.10.15: short lecture & octave exercise

To-do

- Install octave on your notebook
- Bring your notebook to the exercises
Questions and Answers

- Google group:
  - See webpage
  - Same as last year (create new if needed)

- Forum?

- Email:
  - Me about lectures
  - Tutor about exercises
Material

- Slides
- Lecture recordings
- Literature (papers) on the course website
- Thrun et al. “Probabilistic Robotics”
Feedback

Talk to me or send me email!

The earlier you provide feedback the faster and easier things will change...
Questions?