

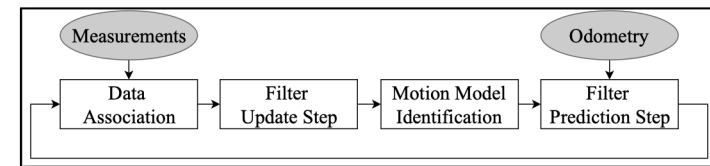
Preliminary Results on 2-D Simultaneous Localization and Mapping for Aerial Robots in Dynamics Environments

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- Design of an extended Kalman filter for simultaneous localization and mapping with moving objects tracking.
- The proposed solution includes tracking and motion model identification of moving objects
- Data fusion is performed without excluding moving objects from the state.
- Simulation results are presented that validate the performance of the filter.



Flowchart of the algorithm