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3 Decision-Theoretic Exploration Using Coverage Maps robot exploration tasks [77]. As mentioned above, our approach uses the entropy to measure the uncertainty about a grid cell. A cell is regarded as been sufficiently observed if the entropy of the coverage belief does not exceed ζ or if it does not change any longer.

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learning SLAM, curse, paper and others. Contribute to liulinbo/slam development by creating an account on GitHub.

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"Robotic Mapping and Exploration" is an important contribution in the area of simultaneous localization and mapping (SLAM) for autonomous robots, which has been receiving a great deal of attention by the research community in the latest few years. The contents are focused on the autonomous mapping learning problem.

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Four Generations of Robotic Mapping and Exploration in

to a vast array of mobile robot mapping problems. The history of robotic mapping is also described, along with an extensive list of open research problems. ... Keywords: Bayes filters, robotic mapping, exploration, expectation maximization algorithm, Kalman filters, mobile robots.

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