

EINLADUNG

Zeit: Donnerstag, 18.01.2007, 16.30 Uhr

Ort: AH I, Ahornstr. 55

Referent: Prof. Dr. Wolfram Burgard, Universität Freiburg

Titel: Probabilistic Techniques for Mobile Robot Mapping
and Exploration

Abstract:

In recent years, probabilistic techniques have enabled novel and innovative solutions to some of the most important problems in mobile robotics. Major challenges in the context of probabilistic algorithms for mobile robot navigation lie in the questions of how to deal with highly complex state estimation problems and how to control the robot so that it efficiently carries out its task. In this talk I will discuss both aspects and present some techniques currently being developed in my group regarding the problem of autonomously learning a map of an unknown environment with a mobile robot. I will first present an efficient approach based on particle filters to solve the simultaneous mapping and localization problem. Then I will describe how this approach can be combined with an exploration strategy that simultaneously takes into account the uncertainty in the pose of the robot and in the map. For all algorithms I will present experimental results, which have been obtained with mobile robots in real-world environments as well as in simulation. I will conclude the presentation with a discussion of open issues and potential directions for future research.

Es laden ein: Die Dozenten der Informatik