

# View-based mapping for wheeled robots

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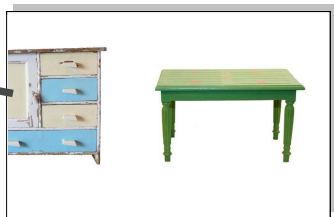




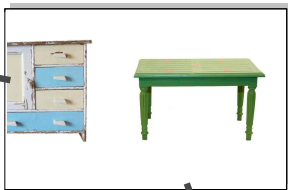


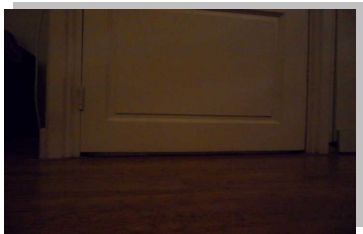
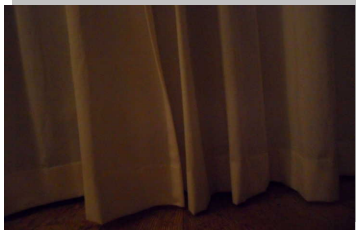
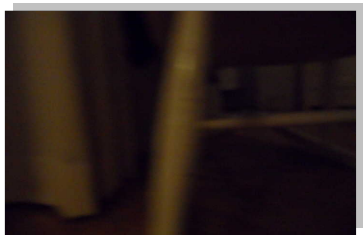


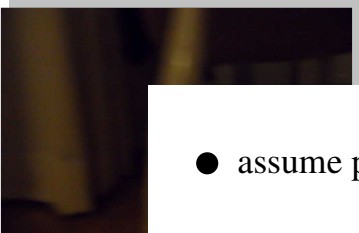
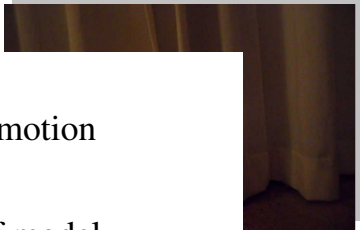
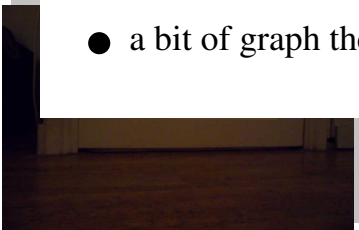










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- assume planar motion
  - learn instead of model
  - a bit of graph theory
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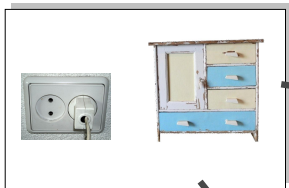
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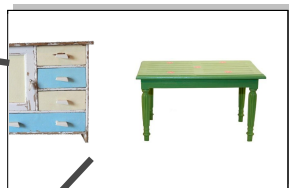
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