View-based mapping for wheeled robots

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25-11-2011

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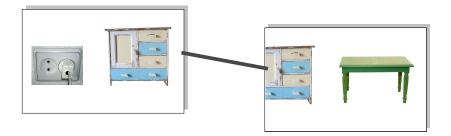
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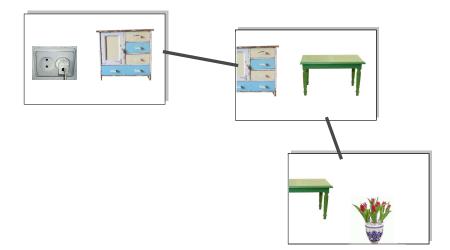




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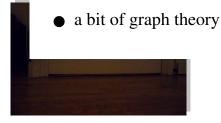
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• assume planar motion

• learn instead of model

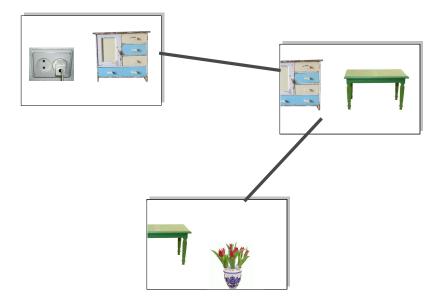
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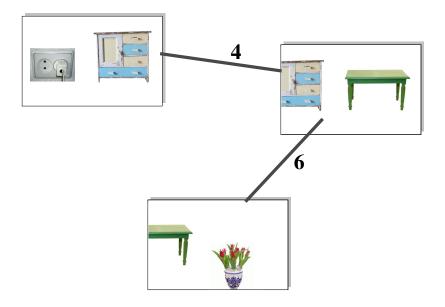












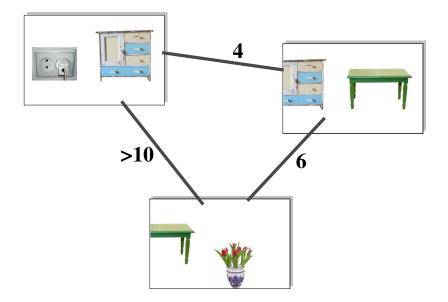
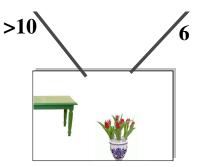




image dissimilarity is not a metric



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