



Closed-loop multi-sensor SLAM using factor graphs for fixed-wing UAV.

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Master Thesis

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Motivation

Develop localization framework which can simultaneously:

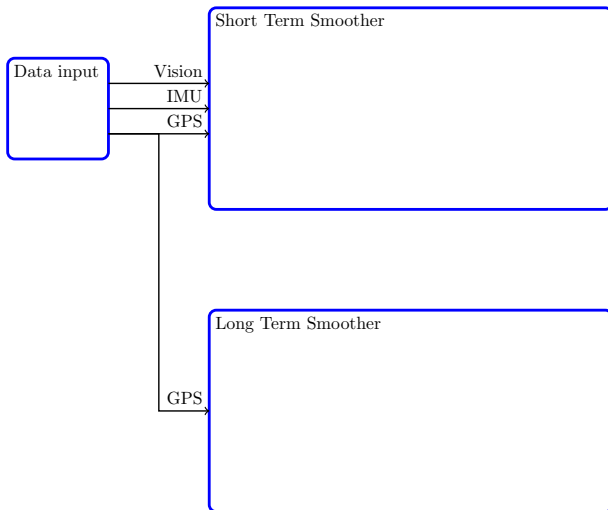
- Estimate local navigation solution with minimal latency
- Find optimal solution given all the measurements

Factor Graph Navigation Framework

Short Term Smoother

Long Term Smoother

Approach



Work done so far

Current challenges

Future work

Overview

Adding a video

Example Slide

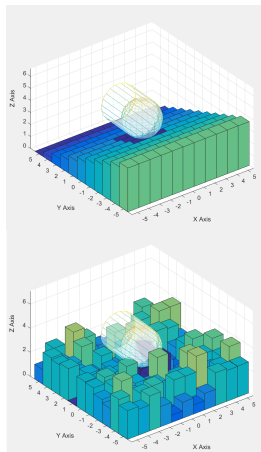
Adding a video



LittleDog walking over rough terrain (S. Schaal, “The latest version of the LittleDog Robot,” 2010. <https://www.youtube.com/watch?v=nUQsRPJ1dYw>)

Adding a video - Example Slide

- Point 1
- Point 2
 - Point 1.1
 - Point 1.2



Caption