

Conclusions - Fast SLAM

- Particle filter SLAM
- Each particle is one path plus one map
- Map features are independent (given the path)
 - one (independent) EKF per feature
 - in contrast to EKF SLAM: no correlations \oplus
 - maintains dependencies only implicitly \ominus
- Each particle uses its own data associations
 - in contrast to EKF SLAM
- Solves both: offline and online SLAM.