

# WearLoc

L. Gemein, D. Speck, A. Biedekapp, R. Gelhausen, J. Nist

April 29, 2016

## Simultaneous Localization and Mapping (SLAM)

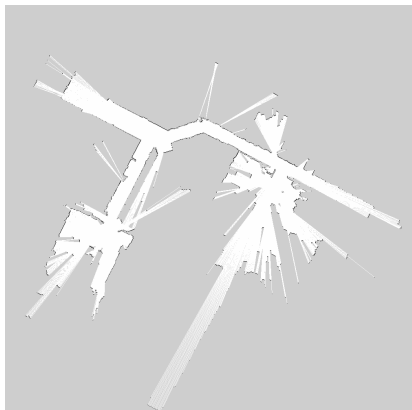
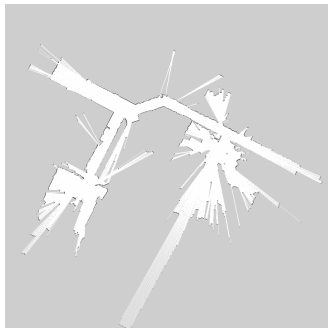


Figure : SLAM: [http://wiki.ros.org/slam\\_gmapping/Tutorials/MappingFromLoggedData](http://wiki.ros.org/slam_gmapping/Tutorials/MappingFromLoggedData)

- Intel Edison
- ROS SLAM
- Laserscanner
- Position sensors



- **04.05.2016: Group presentations**
- 2 weeks: installing ROS + connecting Sensor
- 2 weeks: prepearing data (calibrations) + writing interface
- 1 week: time buffer
- **08.06.2016: Mid-Term Presentations**
  - ⇒ all necessary data available/accessible in ROS
- 2 weeks: first SLAM + calibrations
- 2 weeks: refinements + design
- 2 weeks: time buffer
- **20.07.2016: Final Presentations**
  - ⇒ working WearLoc version + (live presentation)

- Organisation: Jennifer
- Hardware: Lukas and Jennifer
- Data management: André, Rick and David
- ROS: David and Lukas
- Presentation: David, Lukas and Jennifer
- Poster: André
- Paper: Rick

# Backup strategies

- Plan A: Computing on chip Intel Edison
- Plan B: Transmission via wifi to more powerful devices
- Plan C: Collecting data and 'post-computation' on computer