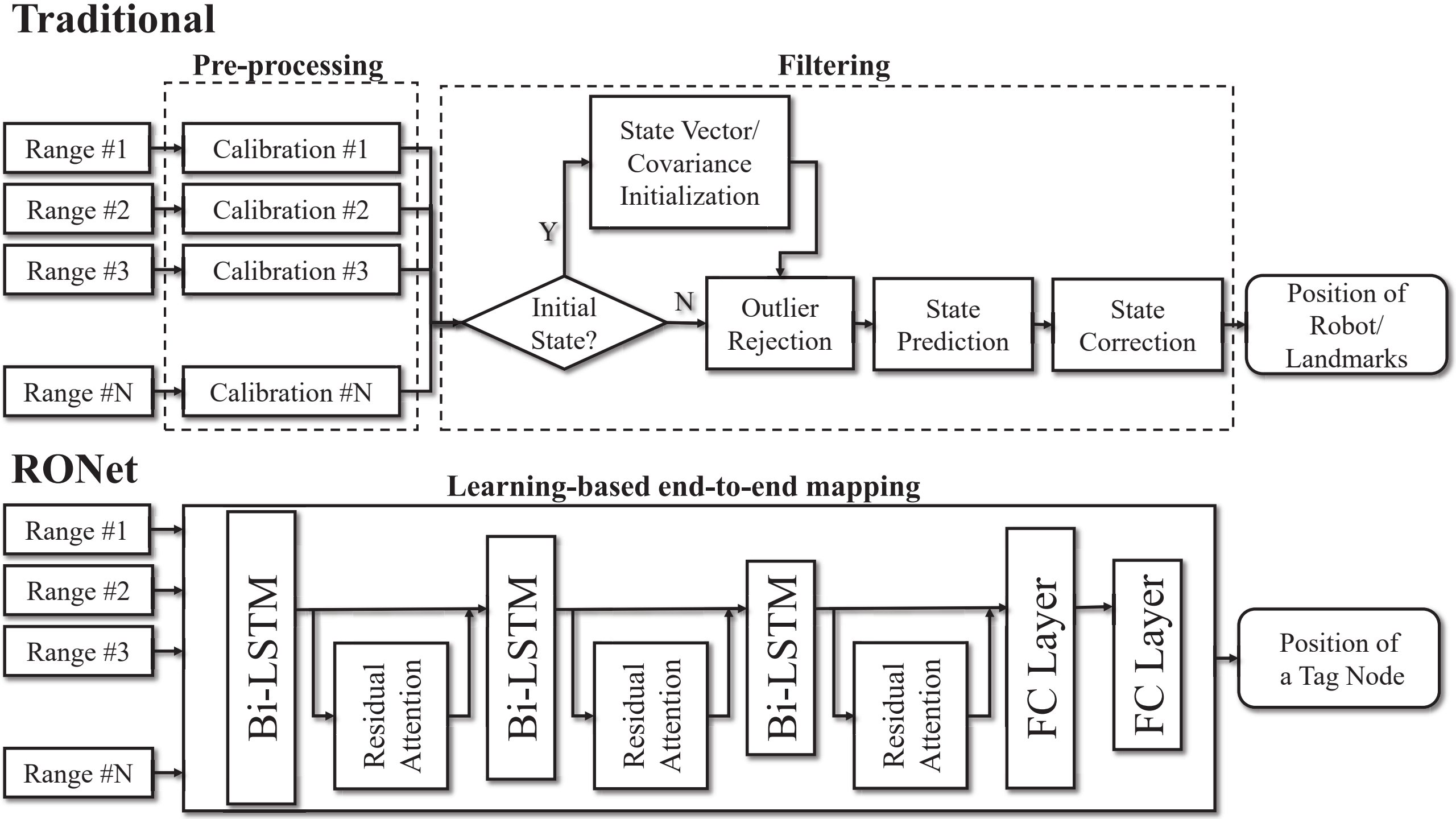
Traditional
Pre-processing
Filtering
Range #1
Range #2
Range #3
Range #N
Calibration #1
Calibration #2
Calibration #3
Calibration #N
State Vector/
Covariance
Initialization
Y
Initial
State?
N
Outlier
Rejection
State
Prediction
State
Correction
Position of
Robot/
Landmarks
RONet
Learning-based end-to-end mapping
Range #1
Range #2
Range #3
Range #N
Bi-LSTM
Residual
Attention
Bi-LSTM
Residual
Attention
Bi-LSTM
Residual
Attention
FC Layer
FC Layer
Position of
a Tag Node