

Localization of Biped Pole-climbing Robots in Spatial Trusses

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- A two-stage localization method based on ultra-wideband (UWB) sensors is proposed.
- The proposed method can locate the robot with a position error less than 100mm and an orientation error less than 5° .
- The proposed method can be applied to global localization of biped pole-climbing robots moving in spatial trusses.

