

A GPU Mapping System for Real-time Robot Motion Planning

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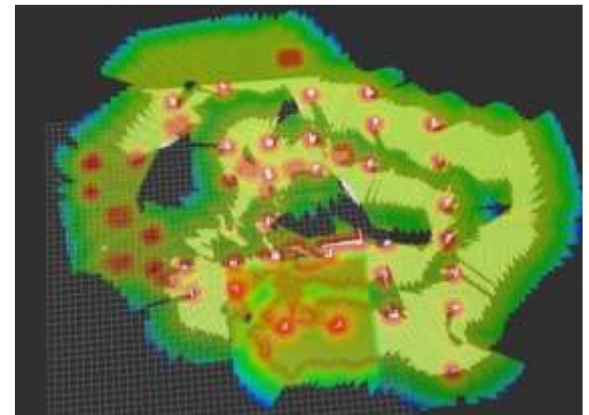
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- Construct Occupancy Grid Maps (OGMs) and Euclidean Signed Distance Fields (ESDFs)
- Optimize the global ESDF storage and address the limited observation problem in an efficient manner
- Can be applied to robotics onboard sensors.
- Propose a real-time robot mapping system on GPU.



Constructing ESDF and OGM