
Sensor Fusion on a mini Unmanned Vehicle

INTEGRATING VISION-BASED ALGORITHMS ON AN ASCTEC PELICAN TO AUTONOMOUSLY
FOLLOW LINEAR SHAPED STRUCTURES IN A LANDSCAPE.

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Abstract

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1 Introduction

1.1 UAV

1.2 Research questions and objectives

The main research question is to find a robust vision-based approach to autonomously navigate over linear shaped structures. This main research question is divided up in the following subquestions:

1. Question
2. Question

1.3 Outline