Simultaneous Localization and Mapping: A General Approach to Different Methods  
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Veysel Erçağlar Yunus Atahan Uğur Can Kozan Melikcan Türkdemir

**I. INTRODUCTION**

Robots in millenium era were always popular. They were popular among both users and researchers. In mobile robots, self driving or observing from outside and processing inside were important. Under heavy research years, Simultaneous Localization and Mapping (SLAM) became extremely popular among researchers. SLAM is a method that on an unknown location, the agent is creating a map concurrently keeping the data of agent’s location. This technique allows a robot to behave like an intelligent being. SLAM is widely used in self-driving cars, and robots that built to make investigation on unknown places to people (Such as MARS). SLAM is preferred because with no prior knowledge robots are still making good progress. There are multiple SLAM algorithms on literature that are beneficial in particular case or not effective. Introduced algorithms for SLAM are as EKF SLAM, Fast SLAM, L-SLAM, GraphSLAM, LSD-SLAM, S-PTAM, ORB-SLAM, MonoSLAM, CoSLAM. There are other algorithms used for SLAM but in this paper, we will try to focus on three of them. At the end of this paper, the implementations will show their comparisons in terms of their efficiency, run time complexity etc.

**II.METHODS**

**2.1 Extended Kalman Filter SLAM**

One of the basic answers for the SLAM was offered by Cheeseman and Smith who processed the EKF to mutually represent the landmark position with the model.[1] It is a class of algorithms that uses Extended Kalman Filter for SLAM problem. EKF is used to estimate the pose of robot and position of landmarks in the map robot moves. Extended Kalman Filter steps is as follows:

* State Prediction:

Estimate new position of the robot

* Measurement Prediction:

Predicting the observation

* Measurement:

Getting real observation with sensors

* Data Association:

Check the difference between predicted observation and real observation that gathered with sensors

* Update:

Change current state (position) of the robot to next state according to the estimation made in data association step.

**REFERENCES**

[1] R. Smith and P. Cheeseman. On the representation and estimation of spatial uncertainty.

*Intl. J. of Robotics Research*, 5(4):56–68, 1987.