

# Probabilistic Qualitative Localization and Mapping

## Supplementary Material

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This document provides supplementary material to the paper [1]. Therefore, it should not be considered a self-contained document, but instead regarded as an appendix of [1]. Throughout this report, all notations and definitions are with compliance to the ones presented in [1].

## 1 Extended Geometrical Analysis

### References

- [1] O. Asraf and V. Indelman. Experience-based prediction of unknown environments for enhanced belief space planning. *IEEE Robotics and Automation Letters (RA-L)*, 2020. Submitted.

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