



Universidade de Aveiro
Mestrado em Robótica e Sistemas Inteligentes
Robótica Móvel

Lesson 8: EKF SLAM

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Nuno Lau/Vitor Santos

In this assignment, you will use the base code provided in `8_rm_mapping.tgz` to complete the implementation of an Extended Kalman Filter SLAM implementation.

1. Read the code of `ekf_slam_landmark.py` and `pyarena/slam/kf_slam_landmark.py`, understand the objective of each method.
2. Check `pyarena/sensors/landmark_sensor.py` and determine which kind of measures are provided by the `LandmarkSensor`.
3. Formulate the problem using an Extended Kalman Filter SLAM approach and complete the implementation of the `run()` method in `pyarena/slam/kf_slam_landmark.py`.

References

[1] <https://github.com/C2SR/pyarena>