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Parallel and Distributed Map Merging and Localization

Algorithms, Tools and
Strategies for Robotic
Networks



Springer

Parallel Distributed Merging Localization Springerbriefs

**Rosario Aragues, Carlos Sagüés, Youcef
Mezouar**

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Parallel and Distributed Map Merging and Localization Rosario Aragues, Carlos Sagüés, Youcef Mezouar, 2015 This work examines the challenges of distributed map merging and localization in multi robot systems which enables robots to acquire the knowledge of their surroundings needed to carry out coordinated tasks. After identifying the main issues associated with this problem each chapter introduces a different distributed strategy for solving them. In addition to presenting a review of distributed algorithms for perception in localization and map merging the text also provides the reader with the necessary tools for proposing new solutions to problems of multi robot perception as well as other interesting topics related to multi robot scenarios. This work will be of interest to postgraduate students and researchers in the robotics and control communities and will appeal to anyone with a general interest in multi robot systems. The reader will not require any prior background knowledge other than a basic understanding of mathematics at a graduate student level. The coverage is largely self contained supported by numerous explanations and demonstrations although references for further study are also supplied.

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