engineering proceedings

Abstract

Aerial Cooperative SLAM for Ground Mobile Robot Path Planning †

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† Presented at the 8th International Symposium on Sensor Science, 17–28 May 2021; Available online: https://i3s2021dresden.sciforum.net/.

Abstract: The trajectory planning for ground mobile robots operating in unknown environments can be a difficult task. In many cases, the sensors used for detecting obstacles only provide information about the immediate surroundings, making it difficult to generate an efficient long-term path. For instance, a robot can easily choose to move along a free path that, eventually, will have a dead end. This research is intended to develop a cooperative scheme of visual-based aerial simultaneous localization and mapping (SLAM) that will be used for generating a safe long-term trajectory for a ground mobile robot. The general idea is to take advantage of the high-altitude point of view of aerial robots to obtain spatial information of a wide area of the surroundings of the robot. In this case, it could be seen as having a zenithal picture of the labyrinth to solve the robot's path. More specifically, the system will generate a wide area spatial map of the ground robot's obstacles from the images taken by a team of aerial robots equipped with onboard cameras, by means of a cooperative visual-based SLAM method. At the same time, the map will be used to generate a safe path for the ground mobile robot. While the ground robot moves, its onboard sensors will be used to refinine the map and, thus, to avoid obstacles that were not detected from the aerial images.

Keywords: visual sensing; autonomous robotics; computer vision; visual SLAM

Citation: Trujillo, J.-C.; Munguia, R.; Grau, A. Aerial Cooperative SLAM for Ground Mobile Robot Path Planning. *Eng. Proc.* **2021**, *6*, 65. https://doi.org/10.3390/I3S2021Dresden-10164

Academic Editors: Gianaurelio Cuniberti and Larysa Baraban

Published: 20 May 2021

Institutional Review Board Statement: Not applicable.

Informed Consent Statement: Not applicable.

Data Availability Statement: Not applicable.