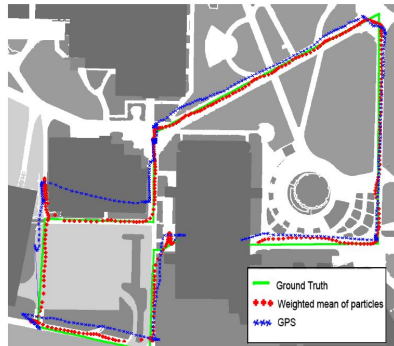
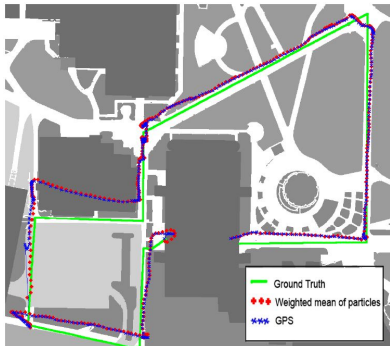


Map-based Priors for Localization

S. M. Oh, S. Tariq, B. N. Walker and F. Dellaert (IROS 2004)



- ▶ Map-based priors for localization using the semantic information available in maps
- ▶ Biases the motion model towards areas of higher probability
- ▶ Easily incorporated in the particle filter by means of a pseudo likelihood under a particular assumption
- ▶ Localization with noisy sensors results in far more stable local tracking
- ▶ Experimental results on a GPS-based outdoor people tracker