



# HiWi or Internship

## 2D/3D Laser Odometry

### ***Description***

One of the biggest problems that are there for accurate robot localization is the inherent inaccuracies of robot odometry based solely on wheel encoders. Therefore it is important to have a redundant source of odometry information. As most industrial robots are already fitted with 2D laser scanners, this information can also be used to register sequential scans to obtain the displacement of the robot between the measurements. This work can also be expanded to implement sensor fusion between the different odometry sources.

### ***Previous Knowledge Required***

C++, ROS

### ***Contact***

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