Abstract

In this paper, an accurate method of updating the configuration pose (dead reckoning) for differential drive mobile robot localization is introduced. This method is based on the principles of geometry. This method ensures the most accurate and fast position updating in comparison with the conventional methods of configuration updating. This method was applied on a group of mobile robots in an indoor environment searching for a target.

References

Albuquerque, NM, 1997.


**Index Terms**

Computer Science  
Applied Sciences

**Keywords**

Dead Reckoning  
Geometry  
Localization  
Navigation  
Mobile Robots.