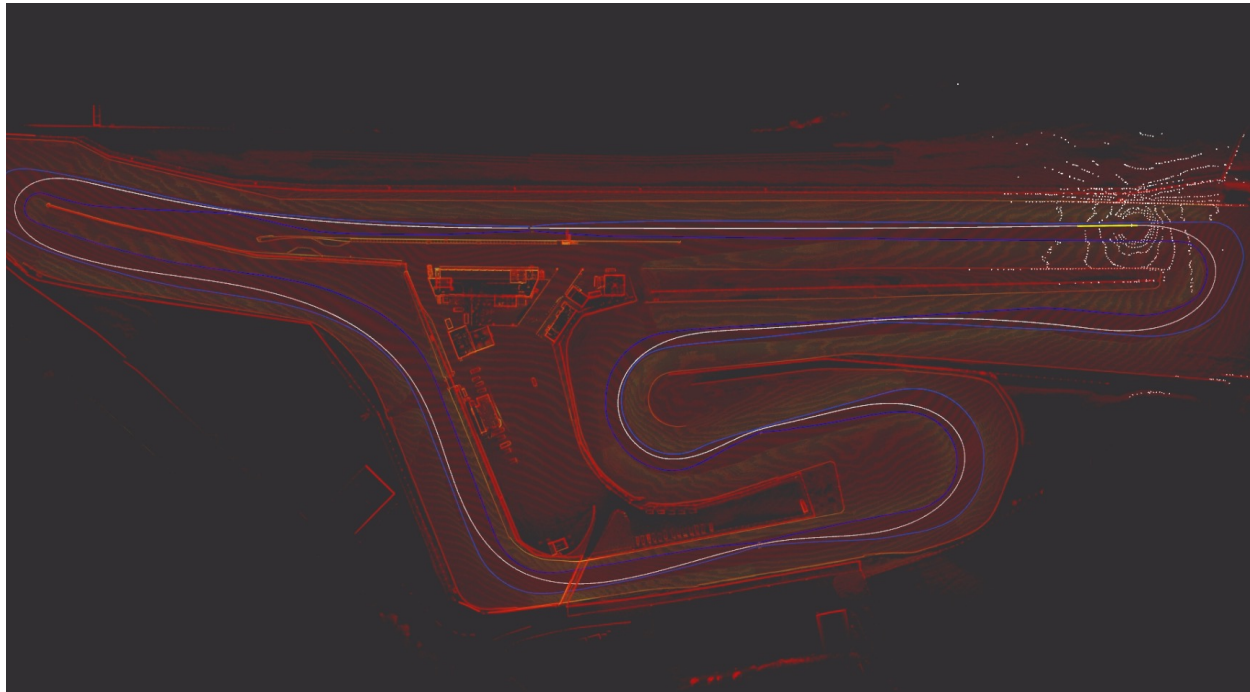


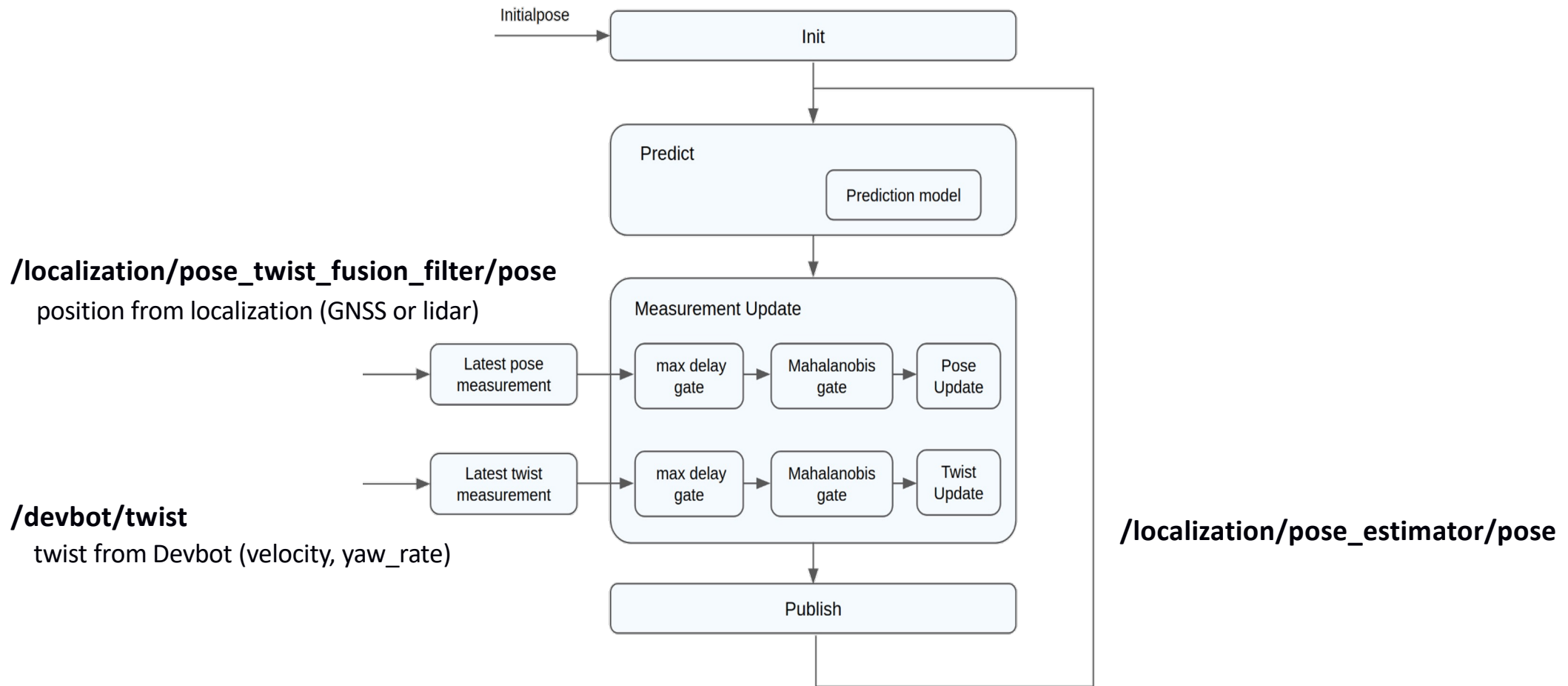
EKF Localization and Fusion

Localization / Roborace / Croix-en-Ternois



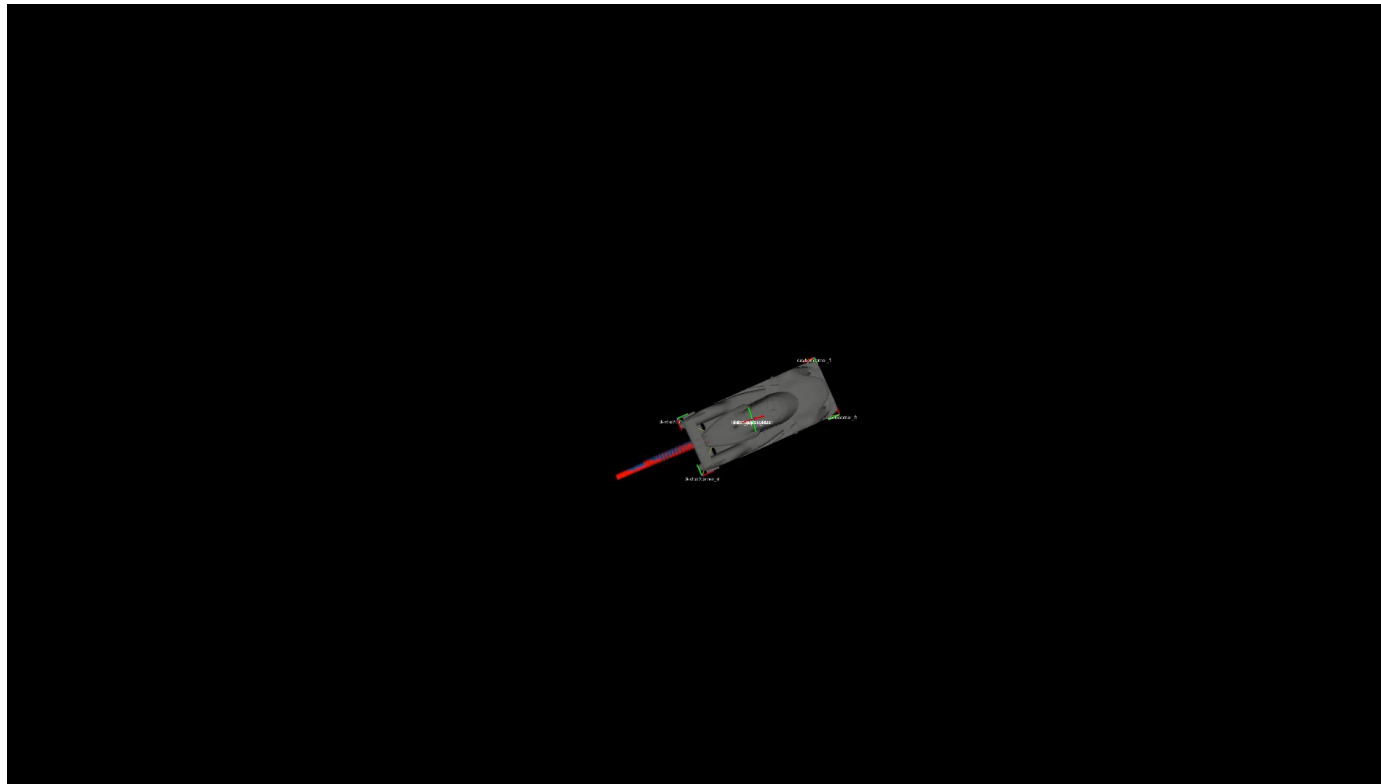
<https://github.com/virtual-vehicle/aa274> [autoware ws](#)

EKF Localizer



Localization with Odometry

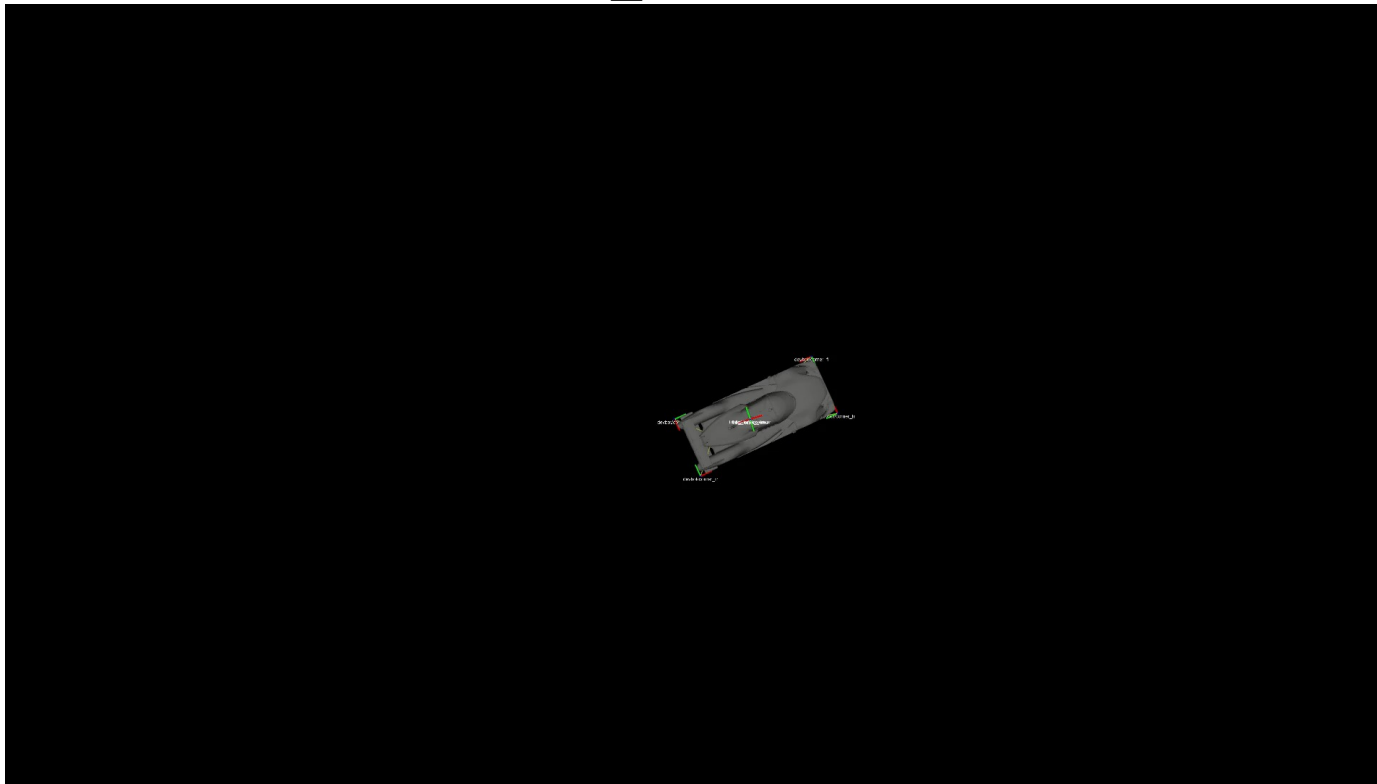
EKF input: `/devbot/twist` (velocity, yaw_rate)



Localization with Odometry and GPS

EKF input: `/devbot/twist`

`/localization/pose_estimator/pose`



Localization with Odometry and GPS

EKF input: /devbot/twist

/localization/pose_estimator/pose (GPS + noise) $N(\mu, \sigma^2)$

$N(0, 5)$

$N(0, 5)$



Localization with Odometry and Lidar

EKF input: `/devbot/twist`

`/localization/pose_estimator/pose` (Lidar)





Thanks for your attention! Questions?

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https://github.com/virtual-vehicle/aa274_autoware_ws