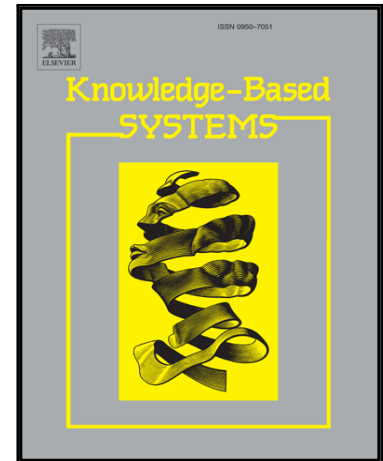


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Building Multiversal Semantic Maps for Mobile Robot Operation

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Highlights

- A probabilistic stance is proposed for tackling the symbol grounding problem.
- The outcome of such grounding is accommodated in a novel semantic map representation.
- This semantic map considers different interpretations of the robot workspace.
- A more coherent robot operation is achieved by exploring such interpretations.
- Our proposal has been assessed employing the Robot@Home dataset.

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