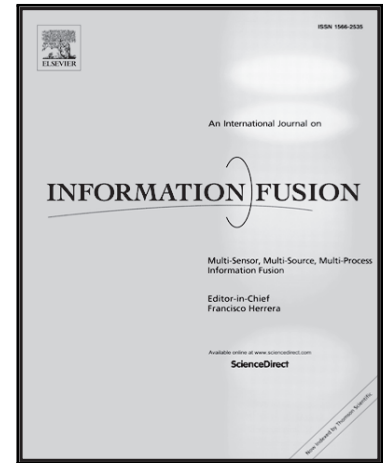


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Cooperative Localization for Disconnected Sensor Networks and a Mobile Robot in Friendly Environments

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Highlights

- An information fusion framework is proposed for robot-sensor network cooperative localization.
- A parallax-based tracking method is designed for sensor nodes to localize the robot.
- Information from both the robot's SLAM and nodes' target tracking is integrated closely.
- Cooperative localization can achieve a better performance than the other methods.

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