

L8-C2 Which filter

Consider the application of an amphibious robot, able to swim in water and walk out of water. To estimate the pose of the robot we defined the state variables as: pose of the head in a large area + angle of each module + type of environment (binary: water or terrain). We want to make a state estimation. Which filter should we use?

- A. Kalman filter, compact**
- B. Particle filter, generic**
- C. Grid-based filter, very generic**



BIOROB, EPFL

