



**Mapping and Localization in Urban Environments
Using Cameras (Schriftenreihe / Institut fuer
Mess- und Regelungstechnik, Karlsruher Institut
fuer Technologie) (Volume 28)**

Henning Lategahn

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In this work we present a system to fully automatically create a highly accurate visual feature map from image data aquired from within a moving vehicle. Moreover, a system for high precision self localization is presented. Furthermore, we present a method to automatically learn a visual descriptor. The map relative self localization is centimeter accurate and allows autonomous driving.

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