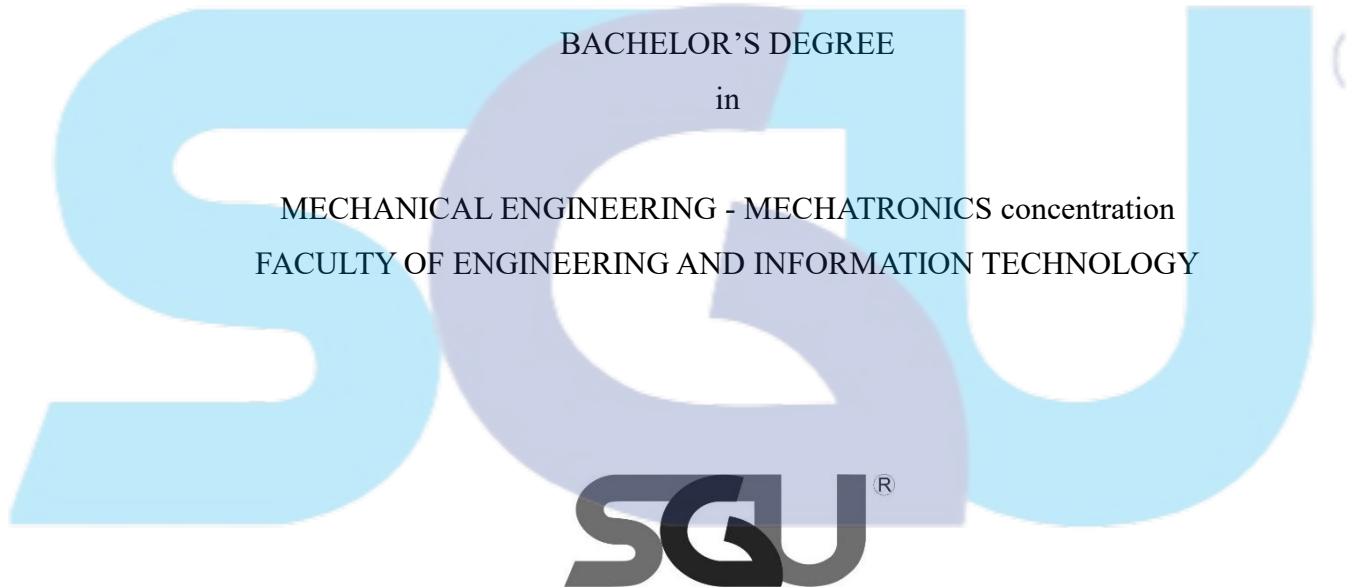


**IMPLEMENTATION OF VISUAL INERTIAL ODOMETRY CONCEPT FOR
OUTDOOR AUTONOMOUS MOBILE ROBOT LOCALIZATION AND
NAVIGATION BASED ON ROS2**

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Revision after the Thesis Defense on 11th July 2023

STATEMENT BY THE AUTHOR

I hereby declare that this submission is my own work and to the best of my knowledge, it contains no material previously published or written by another person, nor material which to a substantial extent has been accepted for the award of any other degree or diploma at any educational institution, except where due acknowledgement is made in the thesis.



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ABSTRACT

IMPLEMENTATION OF VISUAL INERTIAL ODOMETRY CONCEPT FOR OUTDOOR AUTONOMOUS MOBILE ROBOT LOCALIZATION AND NAVIGATION BASED ON ROS2

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Logistical operation in various industries are progressively getting replaced by the utilization of Autonomous Mobile Robots (AMR), that majorly focus on last-mile delivery in an indoor environment. On the other hand, demands of operating AMR in an outdoor scenario gradually increase over time. Thus, this thesis focuses on the development of AMR based on ROS2, that is suitable for operation in outdoor settings, with a specialization of implementing the concept of Visual Inertial Odometry (VIO) by using Intel Realsense T265 tracking camera as an alternative approach for mobile robot localization and navigation that usually utilizes a fusion of mechanically driven rotary encoders and IMU unit. The odometry data generated from the tracking camera displays an idle pose deviation of $\pm 0.05m$ with an average error percentage of 28.60% when subjected to linear movement and operated outdoors under a sunny condition. Ultimately, the outdoor AMR is capable to localize itself by projecting its pose by utilizing the odometry data generated by the tracking camera, with a further integration that successfully enables the operation of autonomous navigation. On the whole, the results of this thesis are feasible as findings and source of data that could be further elaborated on associated mobile robot developments.

Keywords: Autonomous Mobile Robot, Robot Operating System 2, Robot Localization, Robot Odometry, Visual Inertial Odometry.

Dylan Louis



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DEDICATION

I dedicate this work to God,

my family members and dear friends who have supported and inspired me throughout
this challenging journey,

Swiss German University,

and,

the technological advancements in the field of Mechatronics Engineering.

ACKNOWLEDGEMENTS

First and foremost, I am grateful for the wisdom and discernment bestowed upon me during this academic journey. It is through God's guidance that I have been able to navigate the complexities of research, critically analyze information, and make meaningful contributions to my field of study.

I am thankful for my supervisor, Dr. Rusman Rusyadi, B. Sc., M. Sc., for his guidance and expertise, especially in the knowledge of robotics and ROS2. His insightful feedback and constructive criticism have been instrumental in shaping this thesis project and enhancing its quality. Additionally, I would like to extend my heartfelt appreciation for all SGU lecturers, whose collective wisdom and expertise have shaped my understanding to the world of Mechatronics engineering. Their tireless efforts in delivering quality education have been influential in my growth as a scholar. Furthermore, I would be remiss not to mention fellow teaching assistants, especially Mr. Getrich Malvern Tannaka, that through offering valuable insight and help, have supported me throughout this thesis endeavor.

My gratitude extends to my mother and father, whose unconditional love and never ending support have encouraged me to continuously step forward in my life. Their belief in my abilities have given me the strength to overcome challenges and pursue my academic aspirations.

To my friends and colleagues, Hanzen, Elisabet, Sean and others, thank you for your companionship since day one of university, especially Brandon and CE for your logistical support and being really good friends of mine. Lastly, completing this thesis has been a collaborative effort, and I am profoundly grateful to Olivia Dharmadi who has been an exceptional partner. Your emotional, physical, cognitive support, encouragement, and contributions have made this journey bearable and successful. Thank you for being a part in both my academic endeavor and my life.

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