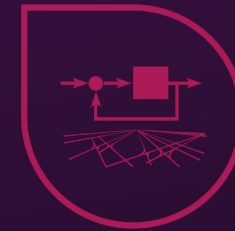


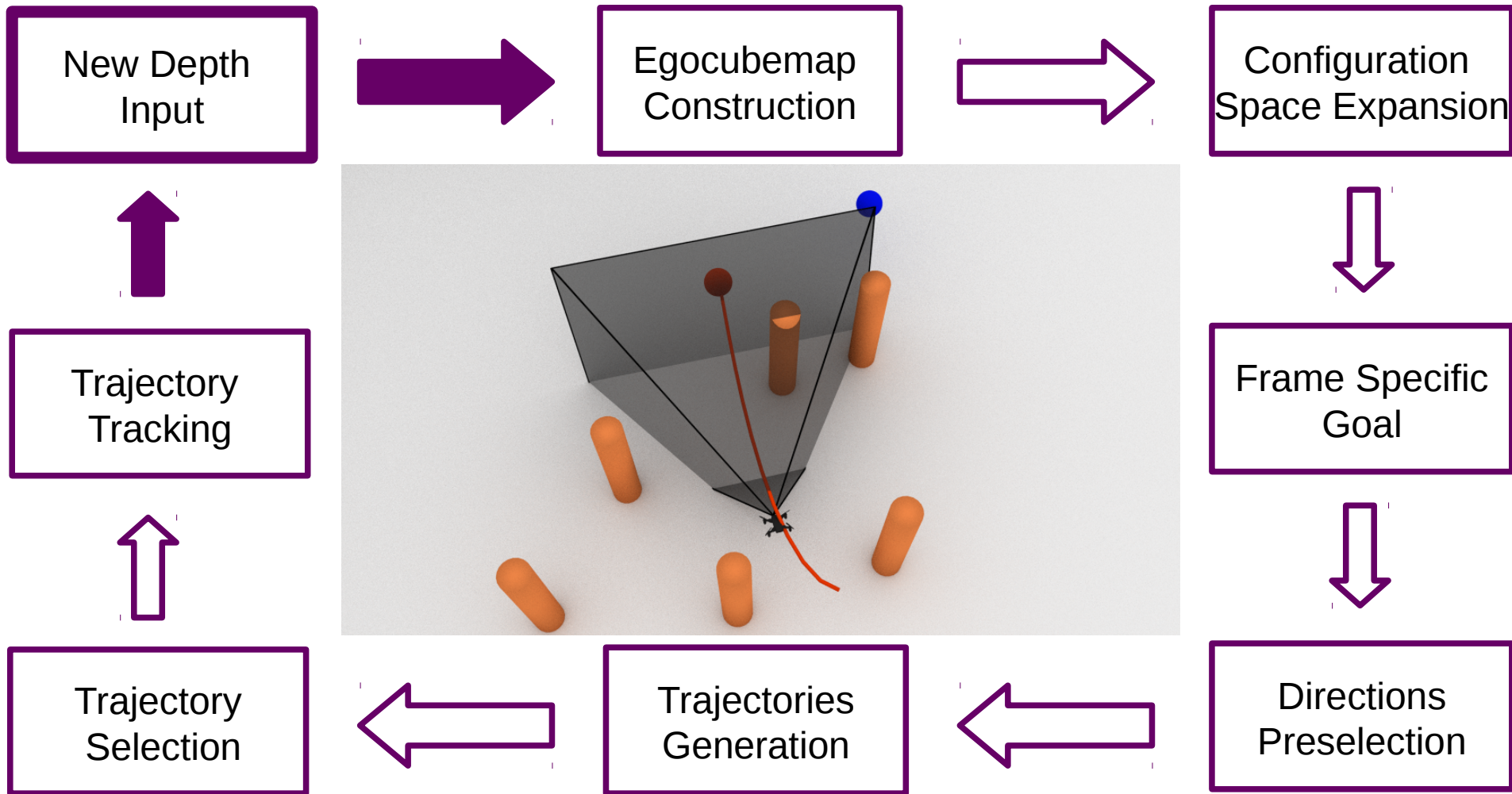


An Egocubemap Based Algorithm for Quadrotors Obstacle Avoidance Using a Single Depth Camera

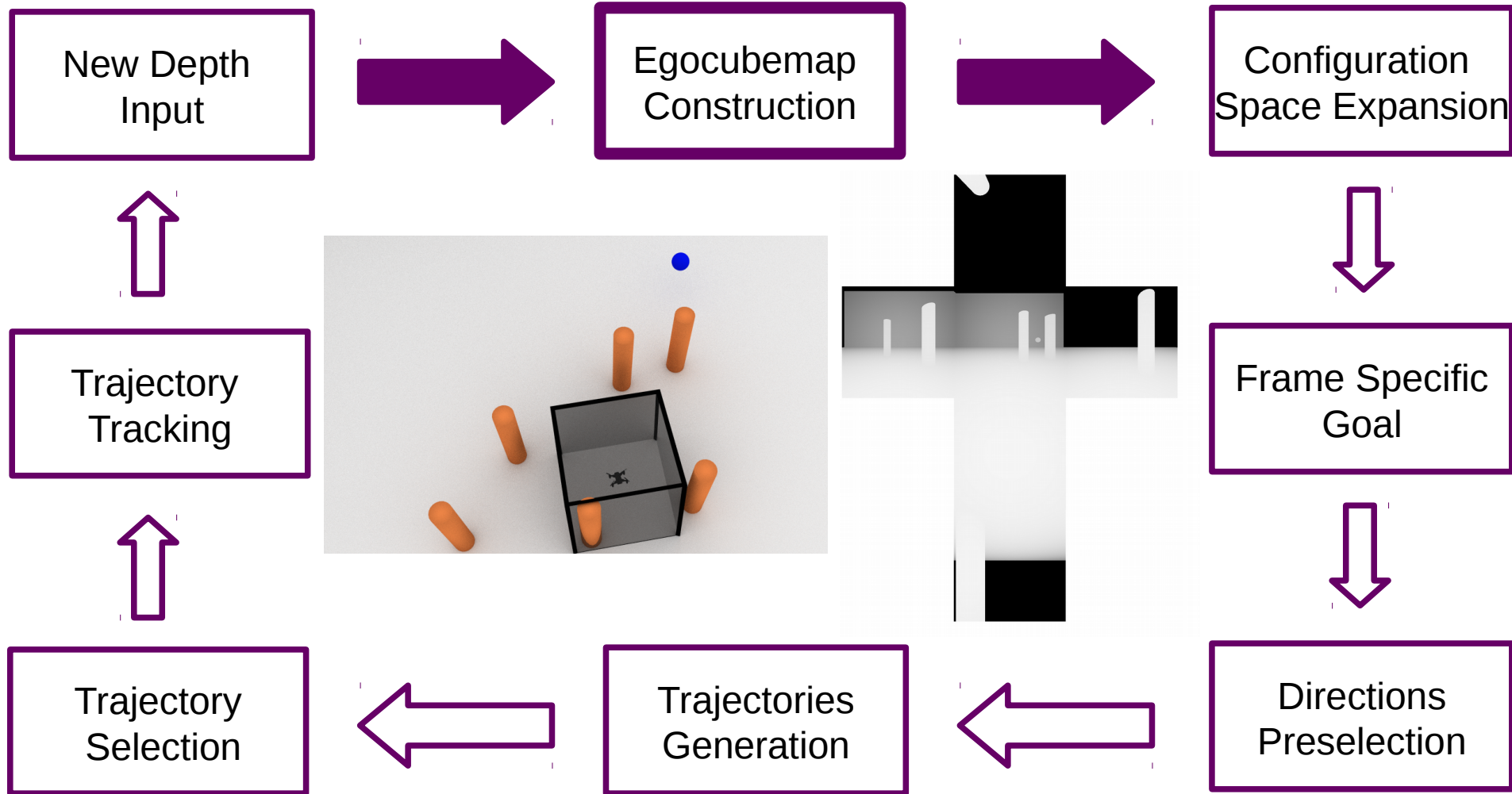
T. Tezenas Du Montcel,
A. Nègre,
M. Muschinowski,
E. Gomez-Balderas
N. Marchand



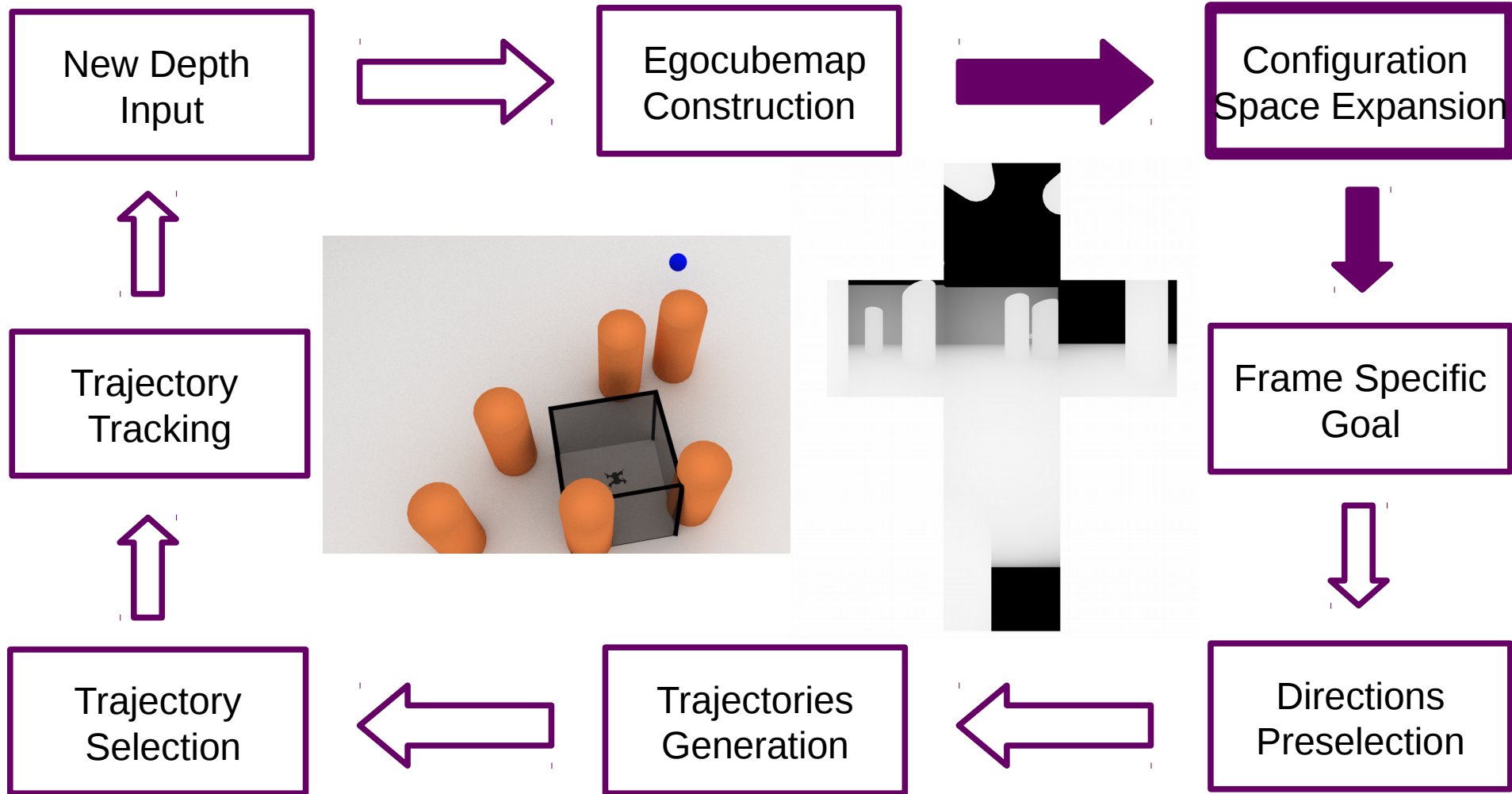
Global Overview of the Algorithm



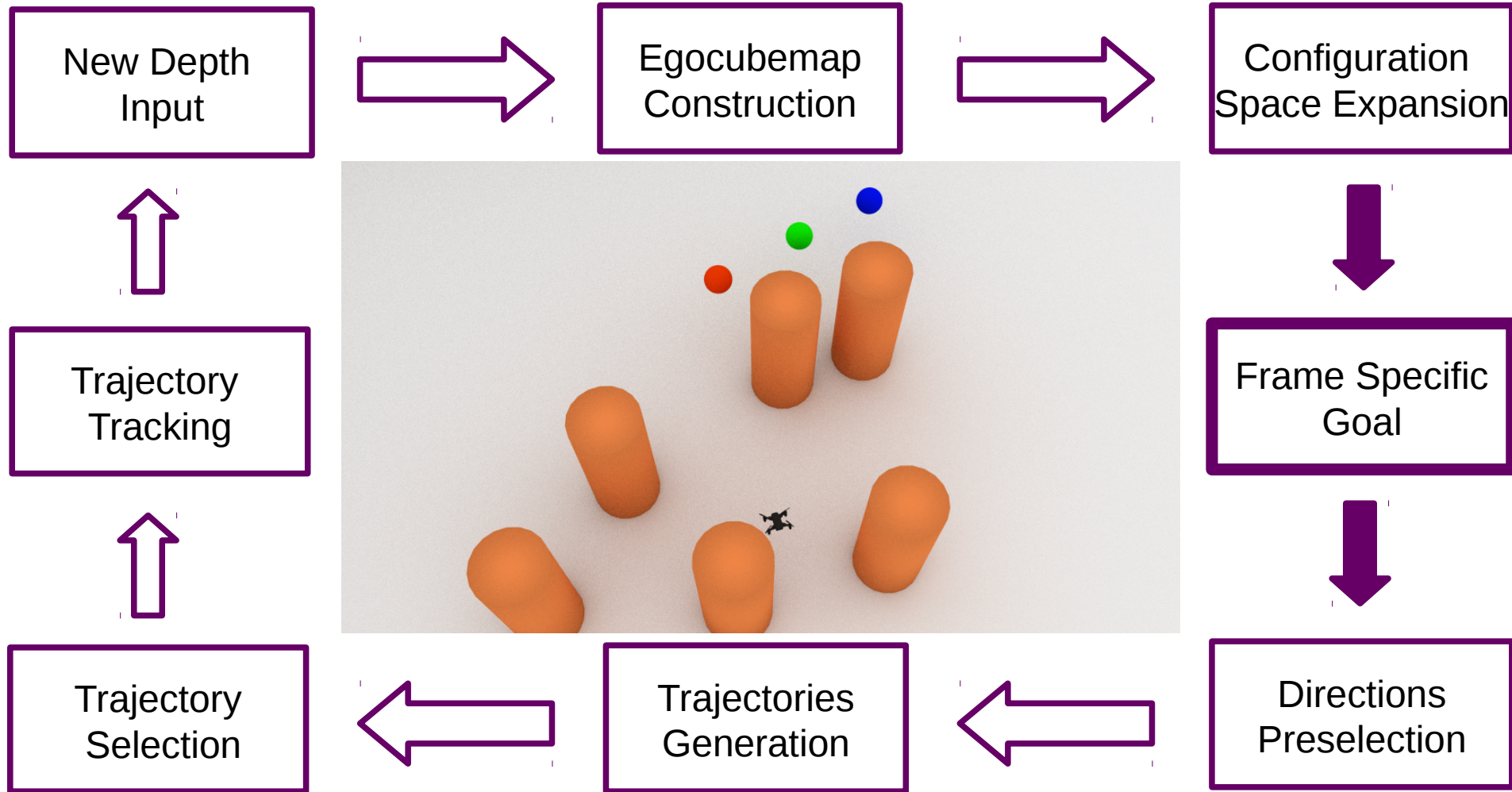
Global Overview of the Algorithm



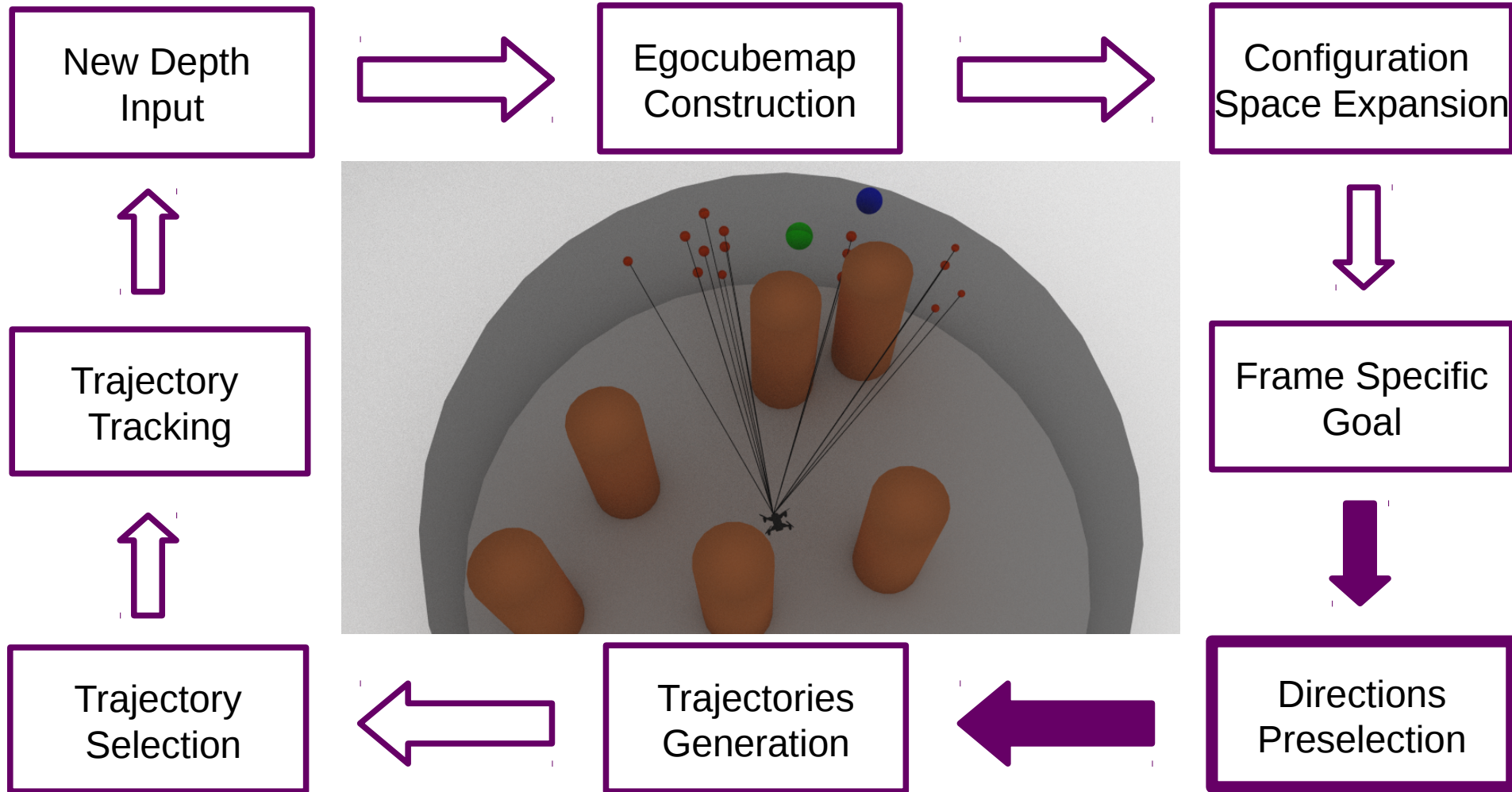
Global Overview of the Algorithm



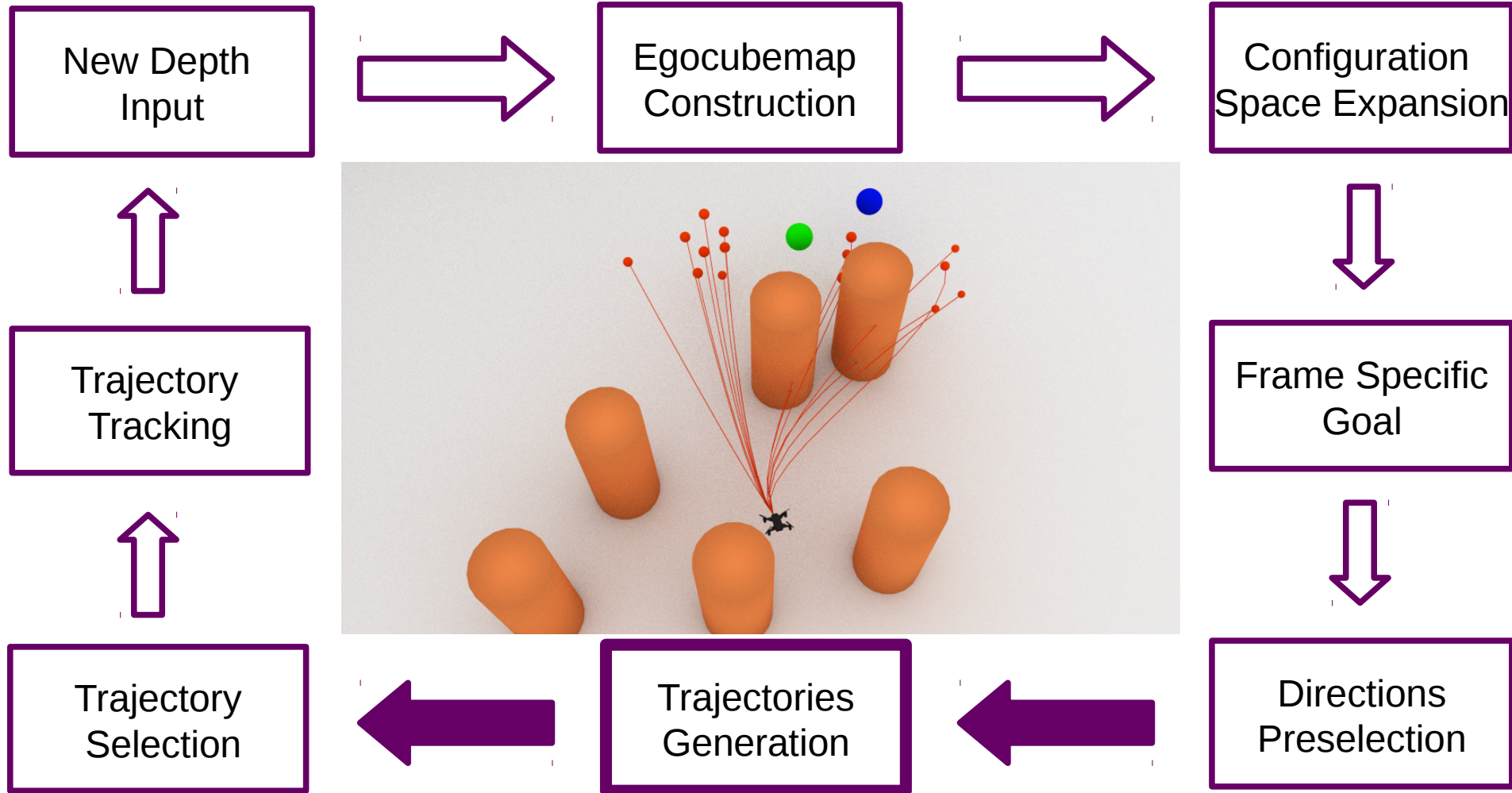
Global Overview of the Algorithm



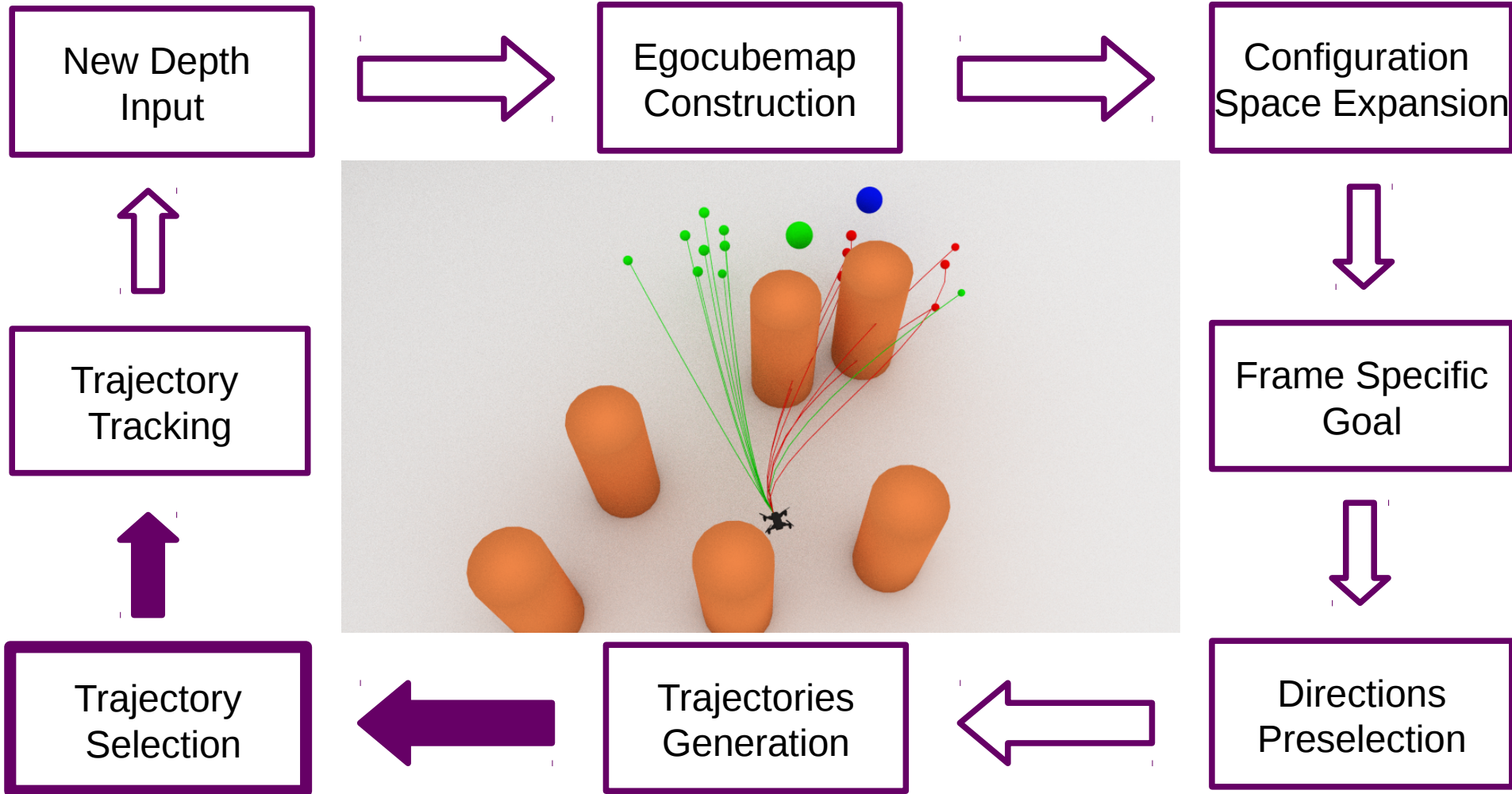
Global Overview of the Algorithm



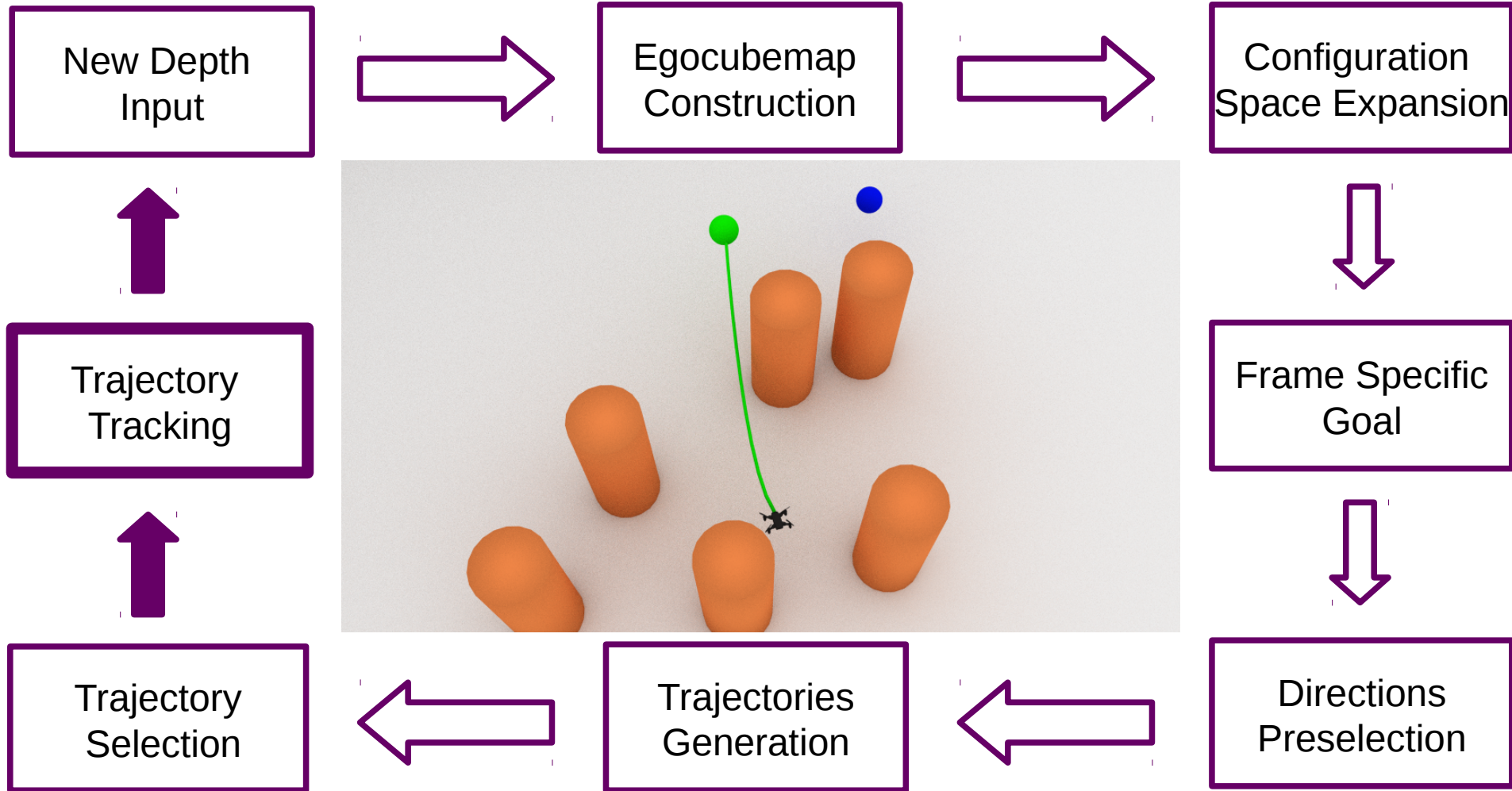
Global Overview of the Algorithm



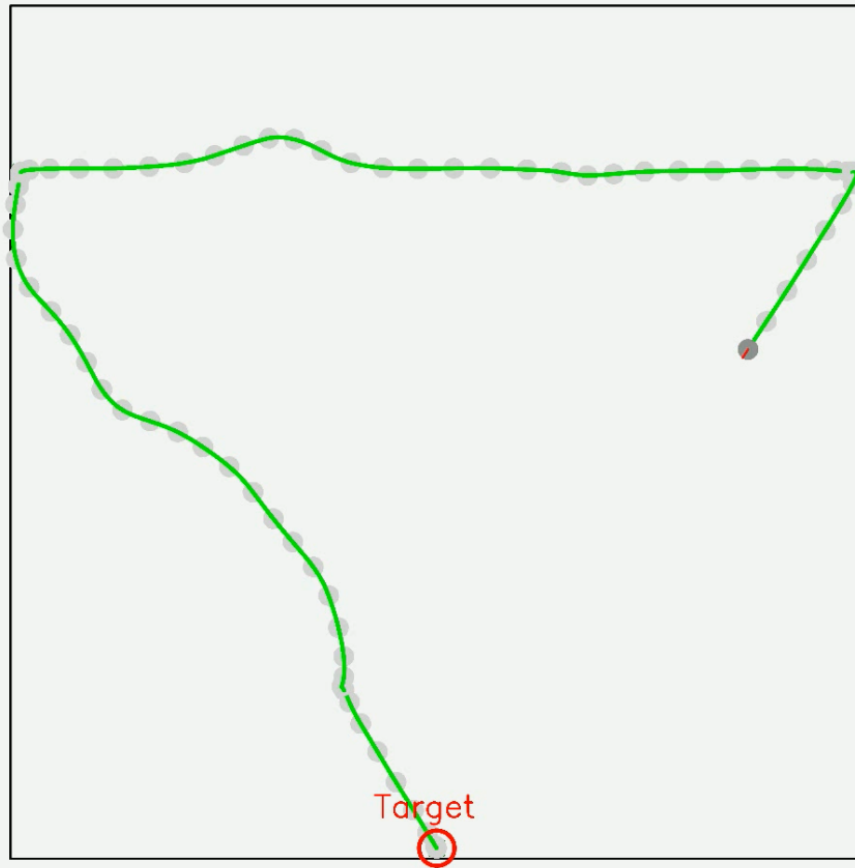
Global Overview of the Algorithm



Global Overview of the Algorithm

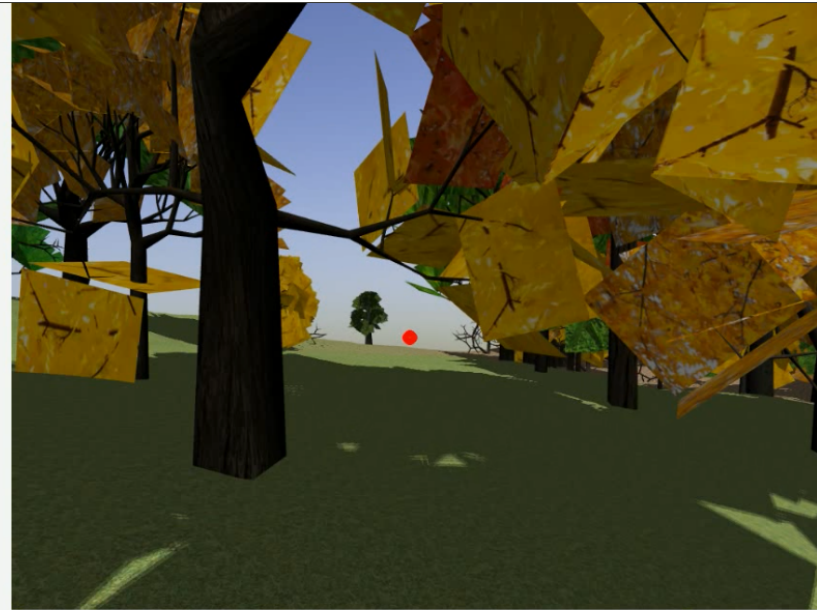


Results



10m

$|v| = 3.58 \text{ m/s}$



Test 75% Completed

Time(s)	E(W)	LinearDist(m)	TotalDist(m)
74.0	0	176.7	185.0

No Collision