

# **Computer vision methods for improved mobile robot state estimation in challenging terrains**

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Journal of multimedia  
2006; 1(7)

## **ARTICLE IDENTIFIERS**

DOI: 10.4304/jmm.1.7.49-61  
PMID: unavailable  
PMCID: not available

## **JOURNAL IDENTIFIERS**

LCCN: not available  
pISSN: not available  
eISSN: 1796-2048  
OCLC ID: not available  
CONS ID: not available  
US National Library of Medicine ID: 101322265

This article was identified from a query of the SafetyLit database.