

Oberflächennormalen erzeugt und klassifiziert. Die erzielten Ergebnisse zeigen, dass mit der verwendeten Methodik Personen robust erkannt werden können. Probleme bereiten vor allem noch relativ viele falsch positive Klassifikationen. Diese konnten durch Verwendung einer Hintergrundkarte zwar reduziert werden, allerdings noch nicht in einem befriedigenden Maße. Probleme bereiteten dabei vor allem die Lokalisierung des Roboters, welche durch die spezifischen Schwierigkeiten der Einsatzumgebung, wie das Überfahren von Teppichkanten, in ihrer Genauigkeit beeinträchtigt wurde. Diese Probleme zu behandeln steht somit im Fokus unserer weiteren Forschungen zu diesem Thema.

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