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Fusion of Multi-Sensors for Underwater Navigation and Localization

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Deadline for manuscript submissions:

closed (28 February 2022)

Message from the Guest Editors

Advances in underwater robotics and autonomous systems have led to the emergence of underwater autonomous vehicles (AUVs) for applications ranging from undersea surveillance through seafloor mapping and seabed characterization to seabed survey and object recognition. At the same time, the scientific community has been deploying unattended systems and sensors at the seafloor or drifting in the water column at increasing depths and for increasing durations. In all these applications, key enabling technologies are navigation and localization. In the former, the vehicle is set to keep track on its planned course and to link findings to a geographic location. In the latter, an accurate estimation of the sensor's location is required not only to confirm the location of the planned deployment, but also to connect findings to the geographic location. In the absence of GPS readings underwater, the deployed system relies on its onboard sensors and on external information for navigation.



mdpi.com/si/69209

Special Issue



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