

# RigidFusion: Robot Localisation and Mapping in Environments with Large Dynamic Rigid Objects

Ran Long<sup>1</sup>, Christian Rauch<sup>1</sup>, Tainwei Zhang<sup>2</sup>, Vladimir Ivan<sup>1</sup> and Sethu Vijayakumar<sup>1</sup>

<sup>1</sup>School of Informatics, University of Edinburgh, U.K.

<sup>2</sup>AIRS, Shenzhen, China

- a dense SLAM method that is robust to large occlusions in the visual input (over 65%),
- simultaneously segment, track and reconstruct the static background and one dynamic rigid body,
- a new RGB-D SLAM dataset with dynamic objects that cause large occlusion and ground truth trajectories.

