1: **Algorithm GraphSLAM_initialize($u_{1:t}$):**

2: $$\begin{pmatrix} \mu_{0,x} \\ \mu_{0,y} \\ \mu_{0,\theta} \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \\ 0 \end{pmatrix}$$

3: *for all controls* $u_t = (v_t \;\; \omega_t)^T$ *do*

4: $$\begin{pmatrix} \mu_{t,x} \\ \mu_{t,y} \\ \mu_{t,\theta} \end{pmatrix} = \begin{pmatrix} \mu_{t-1,x} \\ \mu_{t-1,y} \\ \mu_{t-1,\theta} \end{pmatrix}$$

4: $$+ \begin{pmatrix} -\frac{v_t}{\omega_t} \sin \mu_{t-1,\theta} + \frac{v_t}{\omega_t} \sin(\mu_{t-1,\theta} + \omega_t \Delta t) \\ \frac{v_t}{\omega_t} \cos \mu_{t-1,\theta} - \frac{v_t}{\omega_t} \cos(\mu_{t-1,\theta} + \omega_t \Delta t) \\ \omega_t \Delta t \end{pmatrix}$$

5: *endfor*

6: *return* $\mu_{0:t}$

Table 11.1 Initialization of the mean pose vector $\mu_{1:t}$ in the GraphSLAM algorithm.

1: **Algorithm GraphSLAM_linearize($u_{1:t}, z_{1:t}, c_{1:t}, \mu_{0:t}$):**

2: *set* $\Omega = 0$, $\xi = 0$

3: *add* $\begin{pmatrix} \infty & 0 & 0 \\ 0 & \infty & 0 \\ 0 & 0 & \infty \end{pmatrix}$ *to* Ω *at* x_0

4: *for all controls* $u_t = (v_t \;\; \omega_t)^T$ *do*

5: $$\hat{x}_t = \mu_{t-1} + \begin{pmatrix} -\frac{v_t}{\omega_t} \sin \mu_{t-1,\theta} + \frac{v_t}{\omega_t} \sin(\mu_{t-1,\theta} + \omega_t \Delta t) \\ \frac{v_t}{\omega_t} \cos \mu_{t-1,\theta} - \frac{v_t}{\omega_t} \cos(\mu_{t-1,\theta} + \omega_t \Delta t) \\ \omega_t \Delta t \end{pmatrix}$$

6: $$G_t = \begin{pmatrix} 1 & 0 & -\frac{v_t}{\omega_t} \cos \mu_{t-1,\theta} + \frac{v_t}{\omega_t} \cos(\mu_{t-1,\theta} + \omega_t \Delta t) \\ 0 & 1 & -\frac{v_t}{\omega_t} \sin \mu_{t-1,\theta} + \frac{v_t}{\omega_t} \sin(\mu_{t-1,\theta} + \omega_t \Delta t) \\ 0 & 0 & 1 \end{pmatrix}$$

see next page for continuation