



Figure 9.10 The problem with the standard occupancy grid mapping algorithm in Chapter ??: For the environment shown in Figure (a), a passing robot might receive the (noise-free) measurement shown in (b). The factorial approach maps these beams into probabilistic maps separately for each grid cell and each beam, as shown in (c) and (d). Combining both interpretations yields the map shown in (e). Obviously, there is a conflict in the overlap region, indicated by the circles in (e). The interesting insight is: There exist maps, such as the one in diagram (f), that perfectly explain the sensor measurement without any such conflict. For a sensor reading to be explained, it suffices to assume an obstacle *somewhere* in the cone of a measurement, and not everywhere.