

Computer Vision Based Cooperative Navigation for UAVs and Ground Vehicles

by

Daniel Kamrath

A thesis submitted to the Graduate Faculty of
Auburn University
in partial fulfillment of the
requirements for the Degree of
Master of Science

Auburn, Alabama
August 6, 2022

Keywords: Image Processing, Terrain Relative Navigation, Vehicle Tracking, Cooperative Navigation, Sensor Fusion

Copyright 2022 by Daniel Kamrath

Approved by

Gerry Dozier, Chair, Professor of Computer Science and Software Engineering
Scott Martin, Co-chair, Assistant Research Professor of Mechanical Engineering
David Bevly, McNair Endowed Professor of Mechanical Engineering

This thesis is not approved for public release.