

This paper focuses on object detection and tracking with the help of laser range finder sensor. The paper investigates other author's way of solving similar problems and analysis the problem as it is. The application of the task of robot competition is chosen as the reference problem which is solved as follows. The possible port solution for the non-PC platforms is emphasized. The basis of the solution is built on the idea of Kalman's filters and the identification of the objects according to their position and speed.