No	Subproblems \ TEAM	A	B	C	D	E	Remark
1	Robot simulation	X	X	X	X	X	
2	Velocity Motion Model	X	X			X	
3	Odometry Motion Model			X	X		
4	Beam Model for range finders	X		X		X	
5	Feature-based measurement		X		X		
6	Standard MCL	X	X	X	X	X	
7	MCL variant: KLD-sampling MCL	X	X	X	X	X	
8	Map configuration number	1	2	3	4	5	refer to the dir of maps/
9	Reviewed paper number	2	3	4	5	6	refer to the rpt-sample.pdf
10	Planning under MDP	X	X	X	X	X	