(main) Problem Number	No	Subproblems \ TEAM	A	B	C	D	E	Remark
1	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
2	10	Planning under MDP	X	X	X	X	X	