**The goal of these modes is to find the azimuth of sound or the bearing of such angel where the sound is coming from however as mentioned before the ITD algorithm is efficient to finding around 180 degrees of it bearing starting from 270 till 90 with the time delay giving an angel and the direction of the angel depends on if the value we get is negative positive or in another occasion if the angel is 0 or close to 0, then the target is along 0 or 180 degrees, which is where the 2 part localisation comes using a metronome with bursts of sound it will send sound wave after sound wave, so then the robot would be in listening mode where it is just listening to the sound, once it gets the sound and get the value it will determine based on the value, lets say target is to the right that means the value is positive (depending on how we calculate the value) then the robot turns 90 degrees, it will ignore the angel the first time and think about general direction left, right and forward / back, then the robot will switch to locating this time it will use the same function but will use the angel so if the value was negative 35 it will move 35 degrees to the left leaving it about 55 degrees bearing to original angel , figure below provides better explanation on how this methods finds the angel.**