Weekly report

1. **My *Goals* from last week**
    - **Improve running speed of simulation**
    - **Complete Delaunay triangulation code**
    - **Add Kalman filter**

2. **My *Accomplishments* this week**
    - **Improve running speed of simulation**
    - **Add Kalman filter**

3. **My *Goals* for next week**

My old idea of localization is range based, on the other hand, it is based on odometry. But I found because of system error (sensor error), when the distance between underwater sensor and boat around 200, the mean position of estimation will not change any more. Thus, I try to use range free localization, which use directional transceiver to localize underwater sensor.

- **Complete minimal spanning tree range free localization simulation code**
- **Test the accuracy of result.**

4. **What I need Dr. Becker to do:**
    - **Add a folder on Github for update codes.**
    - **User name: Haoran-Zhao**
    - **Email:zhaohaorandl@gmail.com**