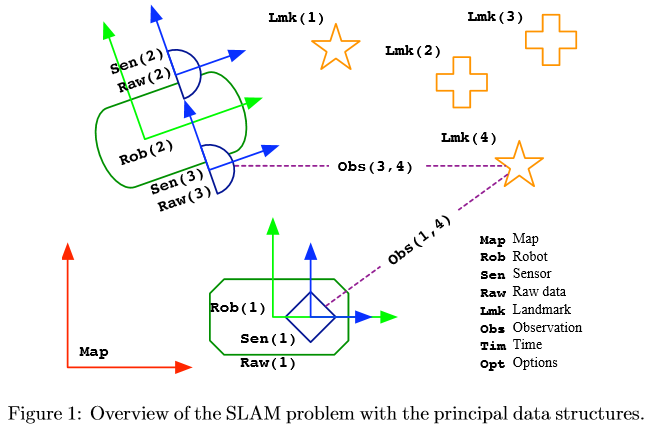
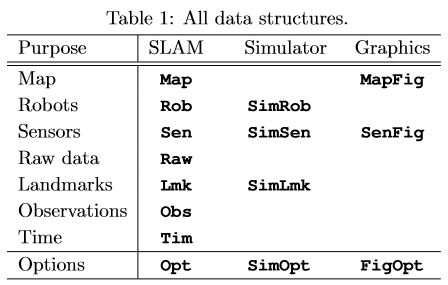
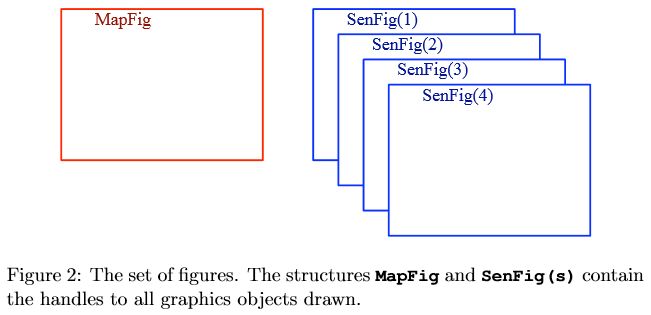
Orientations  is represented by the unit quaternion 

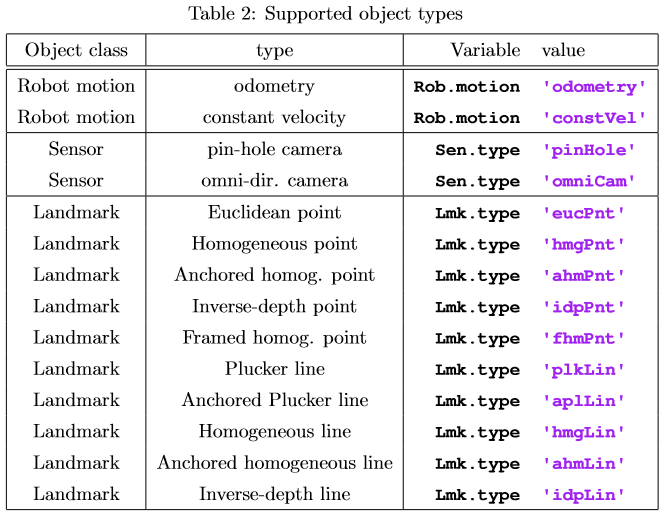
The pose can be specified by: 











all the data related to robot number 2 is stored in Rob(2).

Obs(sen,lmk) stores the data associated to the observation of landmark lmk from sensor sen.

