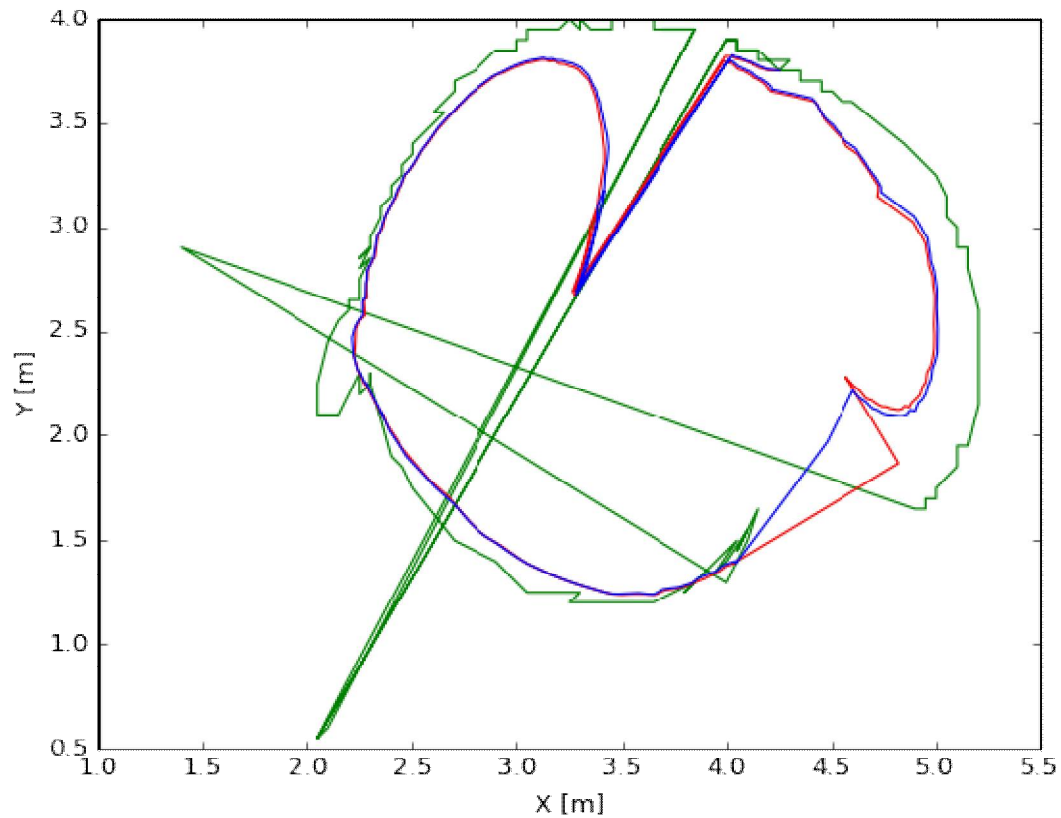


All Code can be found at: https://github.com/chbrock/robotik_ws1718

Aufgabe 1 a

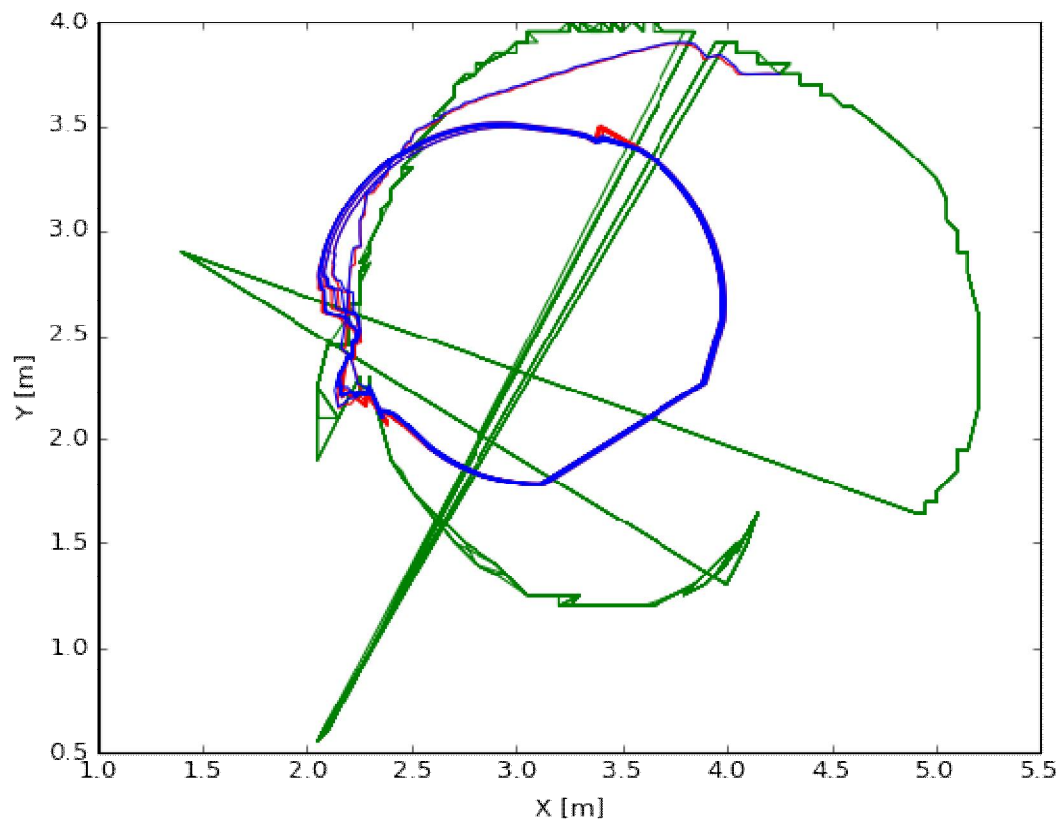


Results for last weeks run using $k = 0.1$:

green: odom_gps, red: predicted positions, blue: updated positions

Aufgabe 1 b

Using more proper filtering results are mixed:



colors as above

Since the radii of the circles in the original odometry and the odom_gps data differ a lot, the final trace sticks close to the prediction, once differences got too large.

Variances for x and y were 0.5 and 0.05 for theta.