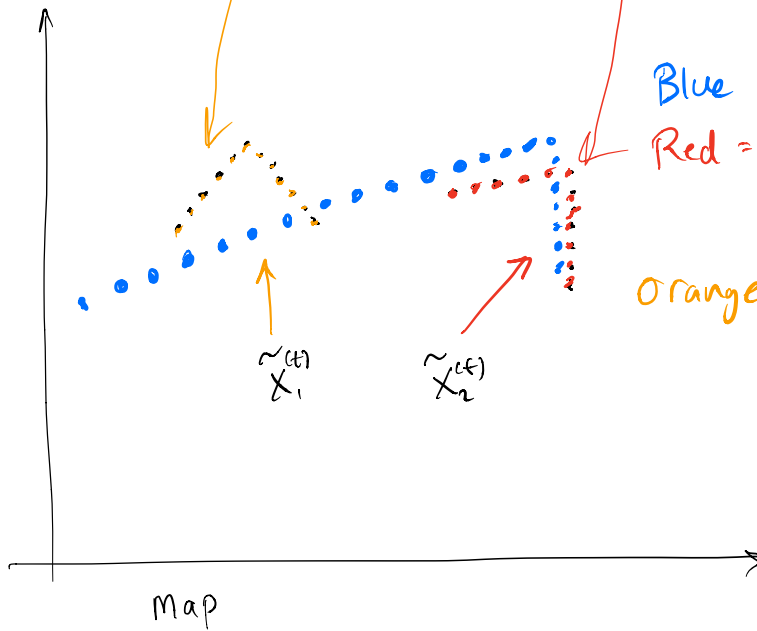


Laser Scan z_t



Data arrives as obstacles detected relative to the robot



Blue = mapped obstacles

Red = laser scan mapped to particle 2 ($\tilde{x}_2^{(t)}$)

Orange = laser scan mapped to particle 1 ($\tilde{x}_1^{(t)}$)