## one\_stationary\_noiseless Experiment Report

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This is a summary of the data from the one\_stationary\_noiseless experiment.

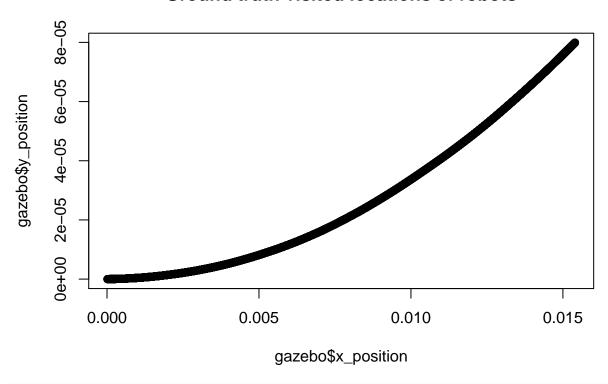
Shown below is the summary of the error of all robots combined for both x and y coordinates, and also the error in total distance.

```
summary(continuous$x_error)
                             Median
                                                   3rd Qu.
         Min.
                 1st Qu.
                                          Mean
## -1.761e-07 -2.481e-09
                          1.910e-09
                                     1.995e-07
                                                9.844e-08
summary(continuous$y_error)
##
                 1st Qu.
                             Median
                                                   3rd Qu.
                                                                 Max.
         Min.
                                          Mean
## -1.531e-10 -8.890e-12 7.027e-12 1.049e-09
                                                1.795e-10 1.136e-08
summary(continuous$dist_error)
                          Median
        Min.
               1st Qu.
                                      Mean
                                              3rd Qu.
## 2.800e-12 2.205e-09 5.193e-09 2.032e-07 1.020e-07 2.186e-06
summary(discrete$x_error)
            1st Qu.
                       Median
                                        3rd Qu.
                                  Mean
## -3.20000 -0.53450 -0.01748 -0.02757
                                        0.63170
                                                 3.45800
summary(discrete$y_error)
##
       Min. 1st Qu.
                       Median
                                  Mean
                                        3rd Qu.
                                                     Max.
## -4.43400 -0.33000 0.06292 0.18060
                                        0.78430
                                                 4.14200
summary(discrete$dist_error)
                              Mean 3rd Qu.
      Min. 1st Qu.
                    Median
                                               Max.
   0.0000 0.3949 1.0320 1.3160 2.0380 4.4980
if (params$robot >= 2) {
    summary(external_data_averages)
```

Shown below are plots representing the robot's motion and error over time.

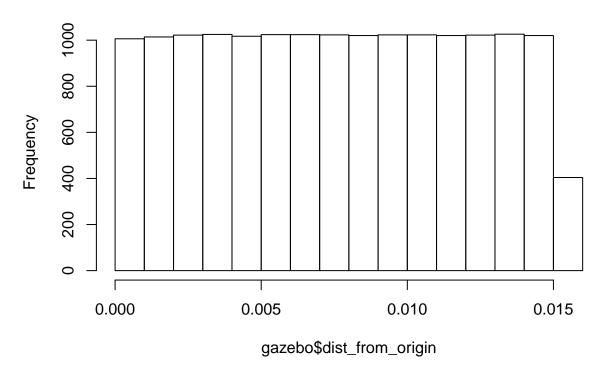
```
plot(gazebo$x_position, gazebo$y_position,
    main = "Ground truth visited locations of robots")
```

#### **Ground truth visited locations of robots**



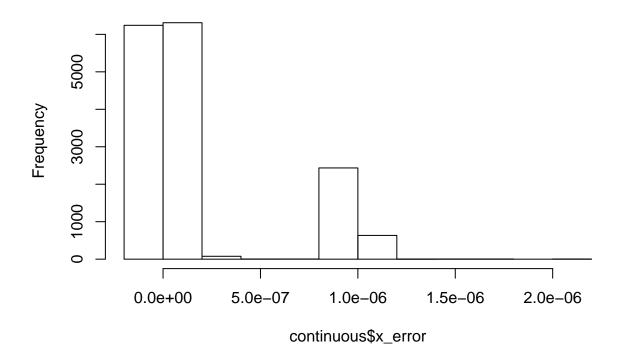
```
hist(gazebo$dist_from_origin,
    main = "Distance from origin vs. time")
```

### Distance from origin vs. time



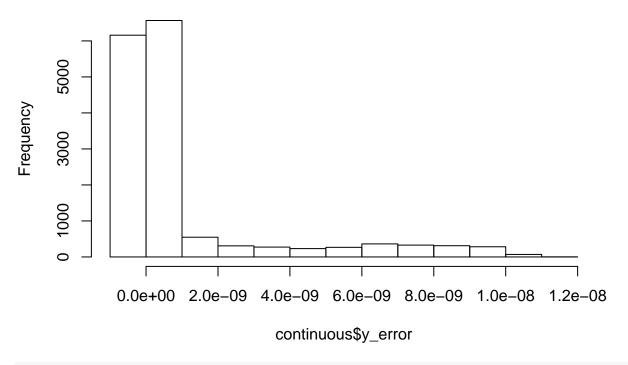
hist(continuous\$x\_error,
 main = "Continuous x\_error")

#### Continuous x\_error



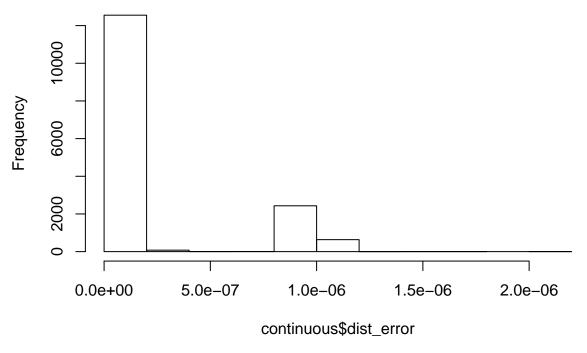
```
hist(continuous$y_error,
    main = "Continuous y_error")
```

### Continuous y\_error

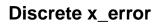


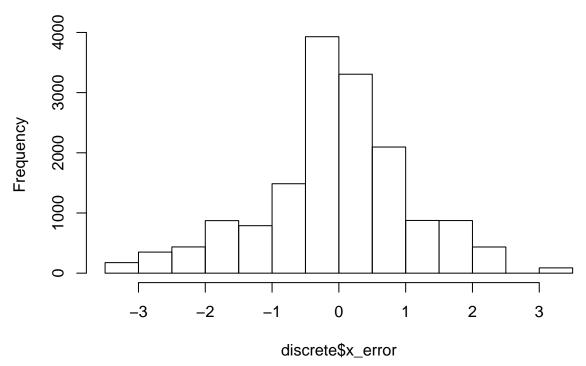
```
hist(continuous$dist_error,
    main = "Continuous total distance error")
```

#### **Continuous total distance error**



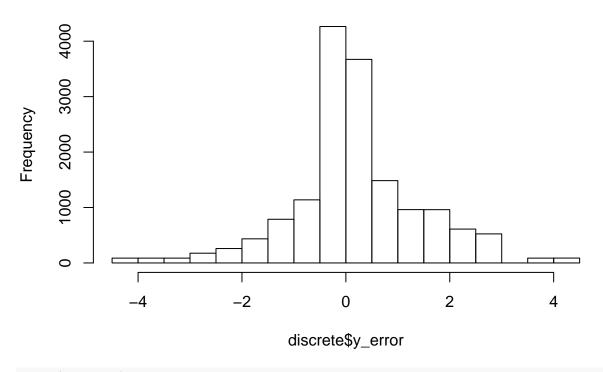
hist(discrete\$x\_error,
 main = "Discrete x\_error")





```
hist(discrete$y_error,
    main = "Discrete y_error")
```

# Discrete y\_error



hist (discrete\$dist\_error,
 main = "Discrete total distance error")

#### Discrete total distance error

