

five_mobile_restricted Turtlebot 1 Report

Matthew Swartwout

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This is a summary of the data from the five_mobile_restricted experiment, Turtlebot #1.

The runtime of this experiment was 0 hours, 1 minutes, and 0 seconds.

The total number of external pose measurements recieved by the robot during this time was 735 which means poses were received at an average of 12.25 poses per second.

Shown below is the summary of each filter's error for both x and y coordinates, and also the error in total distance.

```
summary(continuous$x_error)
```

```
##      Min.    1st Qu.      Median        Mean     3rd Qu.      Max.
## -3.221e-02 -1.217e-03  1.000e-06  4.518e-05  1.173e-03  1.997e-02
```

```
summary(continuous$y_error)
```

```
##      Min.    1st Qu.      Median        Mean     3rd Qu.      Max.
## -0.0390100 -0.0008275 -0.0000065  0.0002826  0.0021870  0.0192700
```

```
summary(continuous$yaw_error)
```

```
##      Min.    1st Qu.      Median        Mean     3rd Qu.      Max.
## -6.283000 -0.060920 -0.003129 -0.063540  0.014680  6.233000
```

```
summary(continuous$dist_error)
```

```
##      Min.    1st Qu.      Median        Mean     3rd Qu.      Max.
## 1.400e-07 2.884e-04 2.799e-03 5.495e-03 8.785e-03 3.901e-02
```

```
summary(discrete$x_error)
```

```
##      Min.    1st Qu.      Median        Mean     3rd Qu.      Max.
## -3.733000 -0.061390  0.000213  0.209500  0.327300  3.563000
```

```
summary(discrete$y_error)
```

```
##      Min.    1st Qu.      Median        Mean     3rd Qu.      Max.
## -1.723000 -0.000348  0.032690  0.451400  0.895000  3.247000
```

```
summary(discrete$yaw_error)
```

```
##      Min.    1st Qu.      Median        Mean     3rd Qu.      Max.
## -6.209000 -0.192400 -0.000497 -0.137700  0.011580  4.859000
```

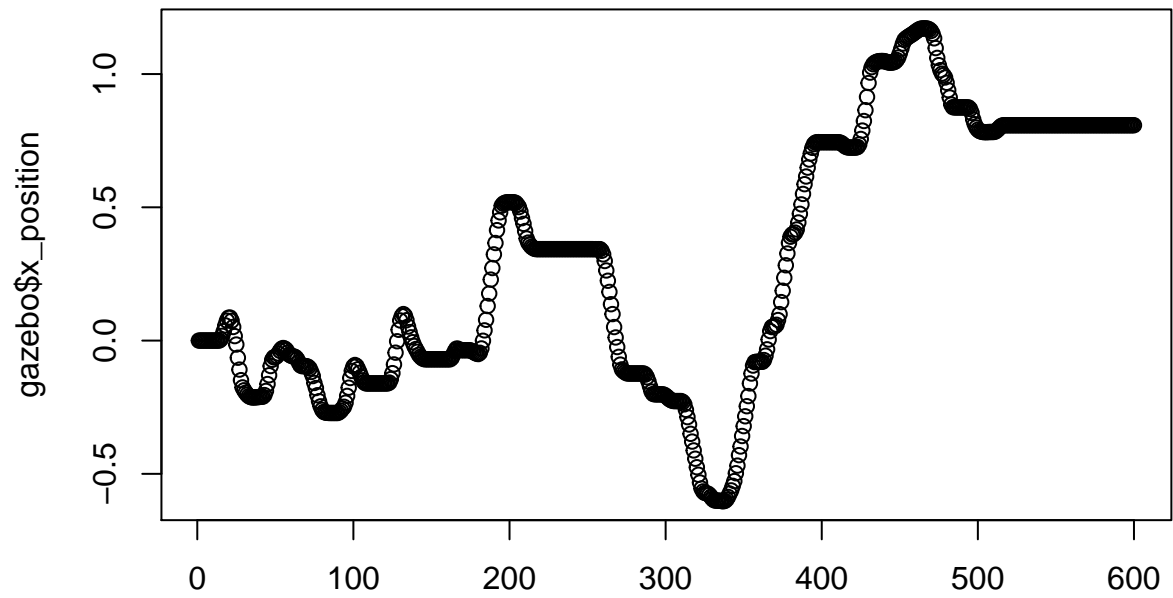
```
summary(discrete$dist_error)
```

```
##      Min.    1st Qu.      Median        Mean     3rd Qu.      Max.
## 0.000000 0.02299 0.31900 0.96280 1.79700 3.94500
```

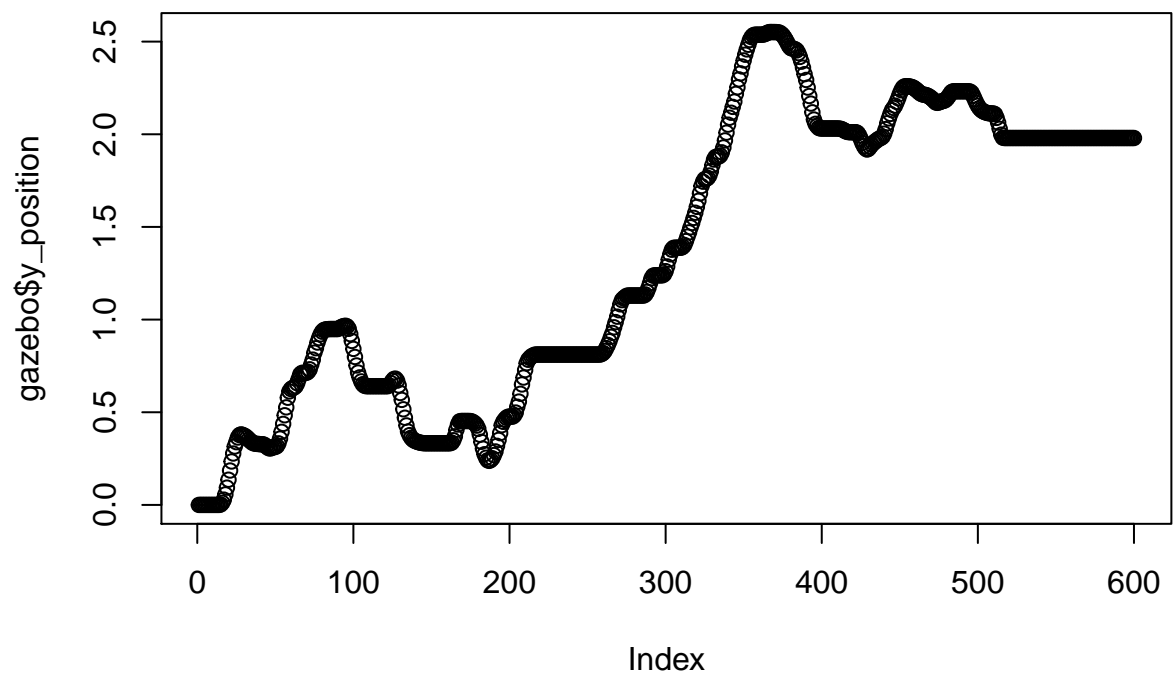
```
#sum(continuous$dist_error <= 0.25) / length(continuous$dist_error)
```

```
#sum(discrete$dist_error <= 0.25) / length(discrete$dist_error)
```

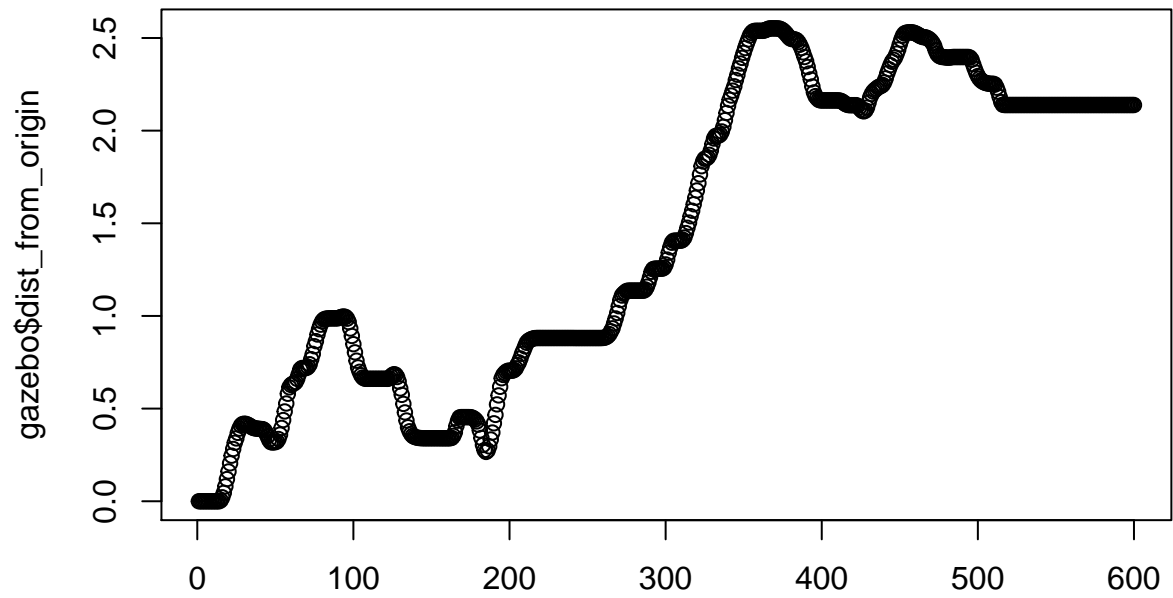
X coordinate of robot over time



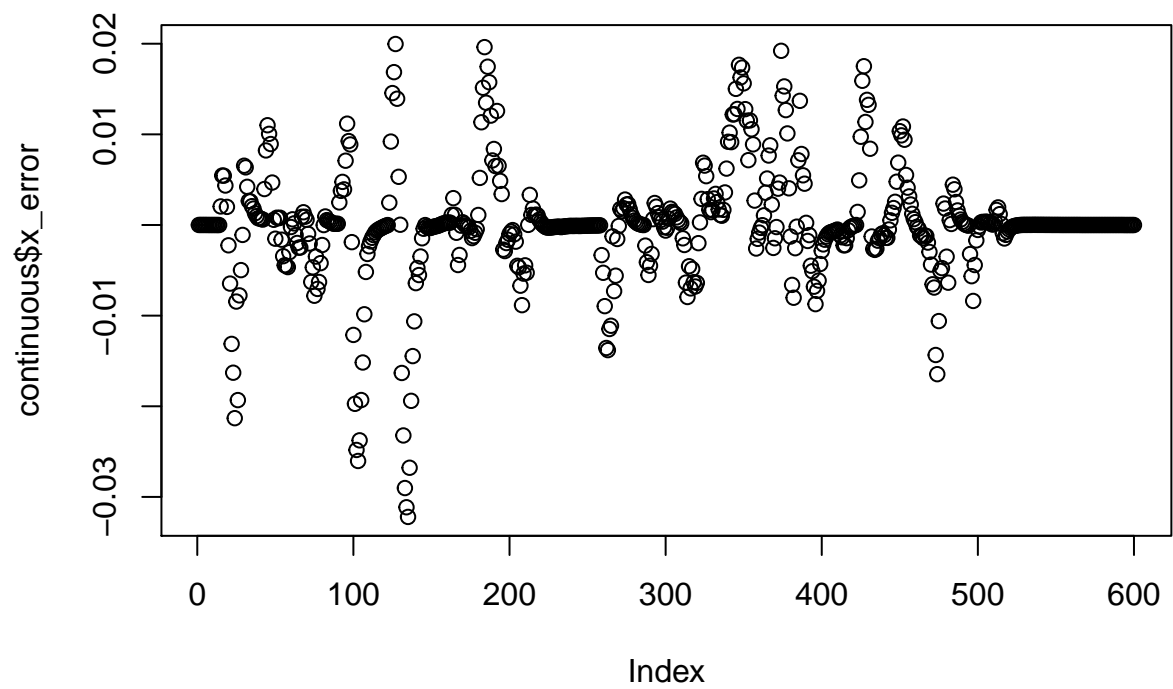
Y coordinate of robot over time



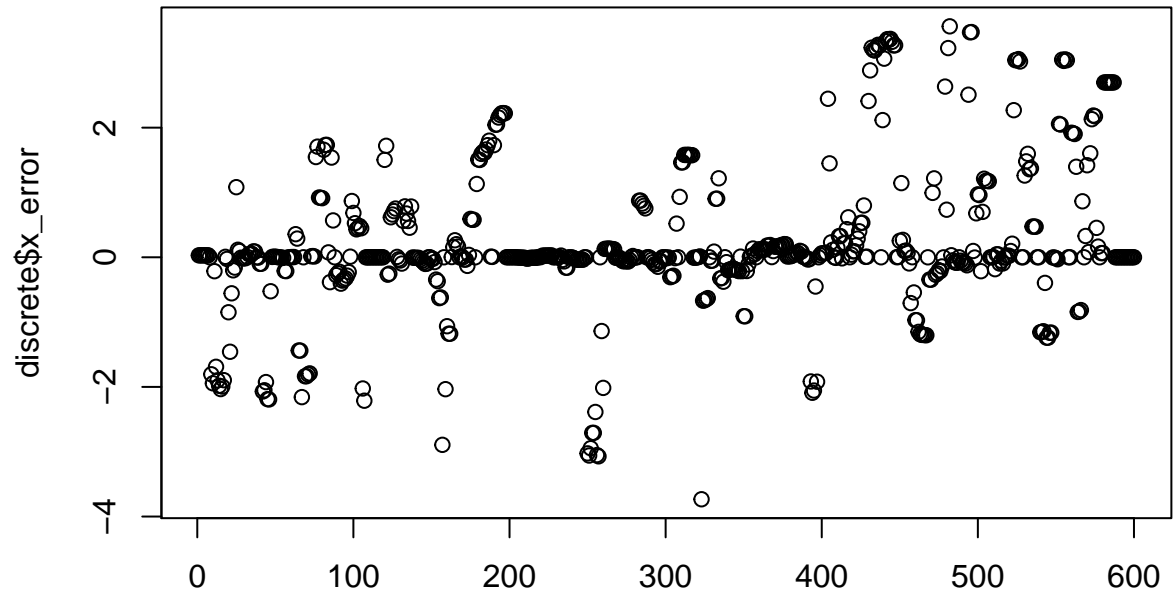
Distance from origin vs. time



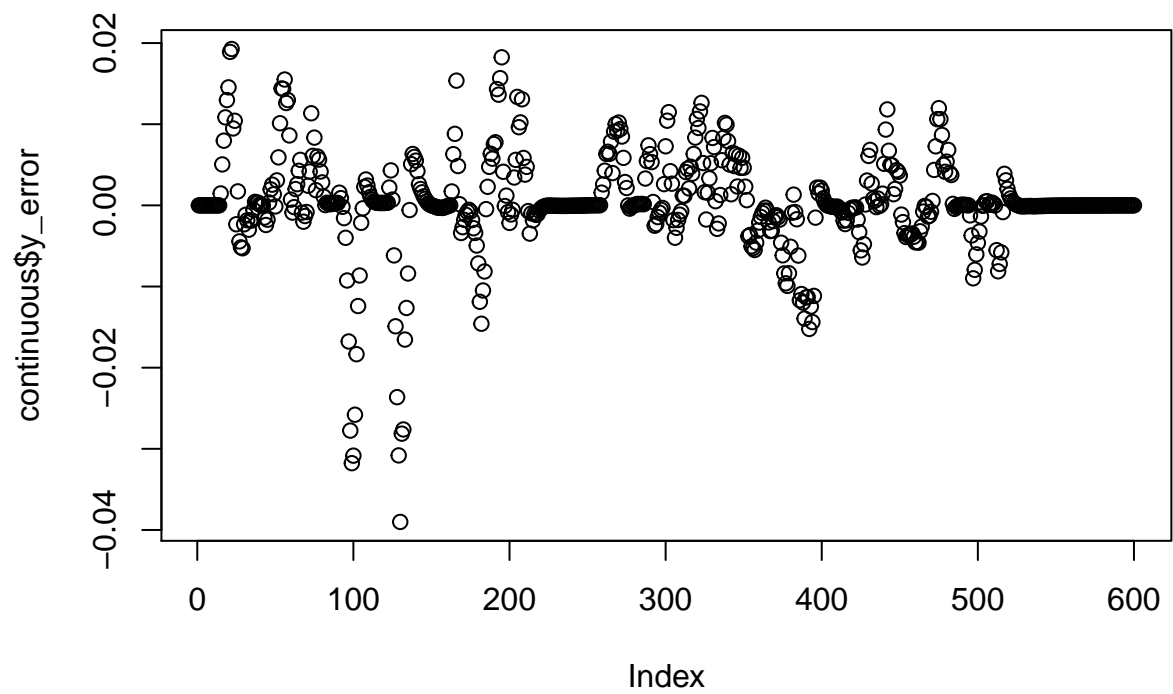
Continuous x_error over time



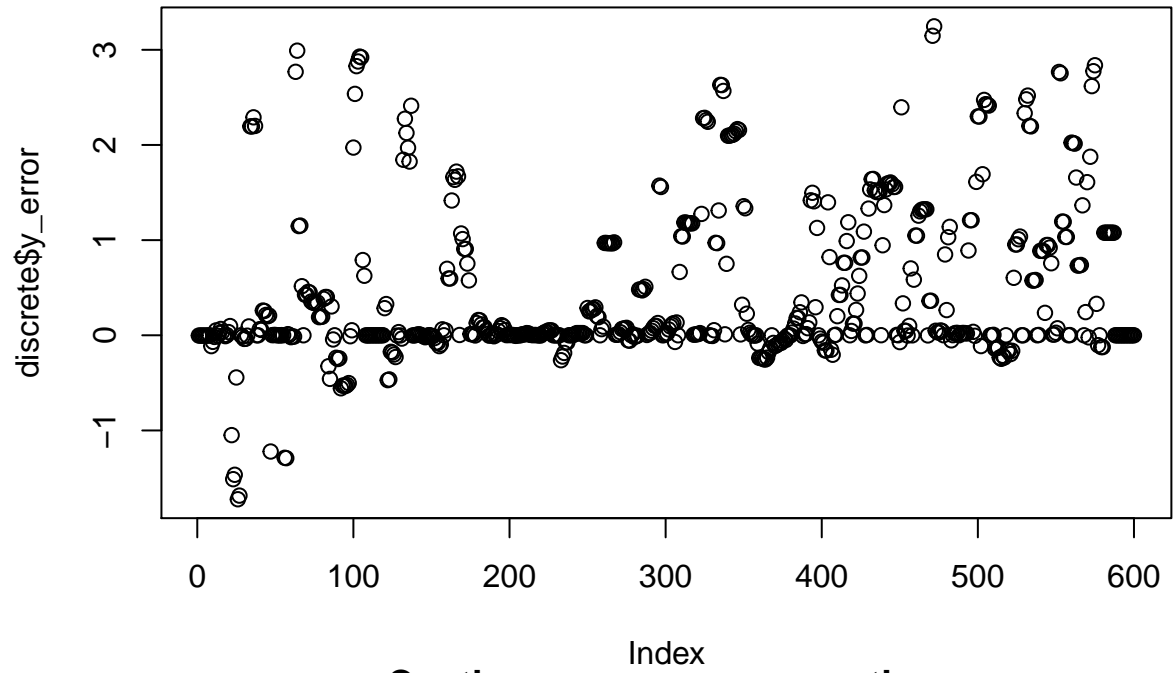
Discrete x_error over time



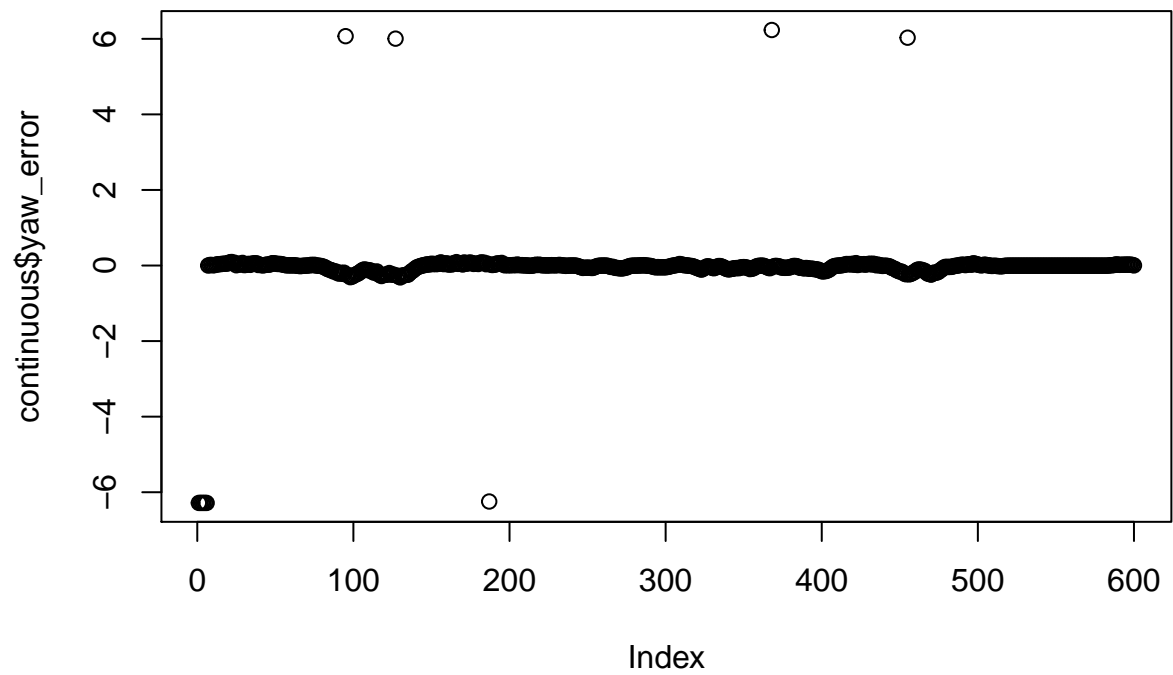
Continuous y_error over time



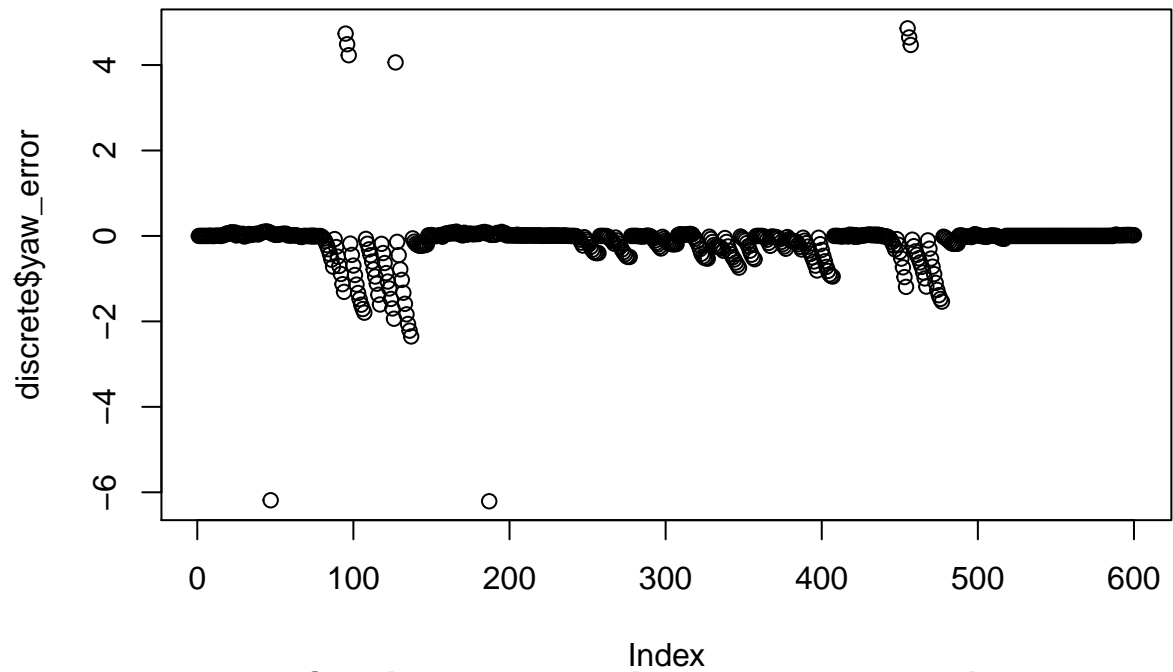
Discrete y_error over time



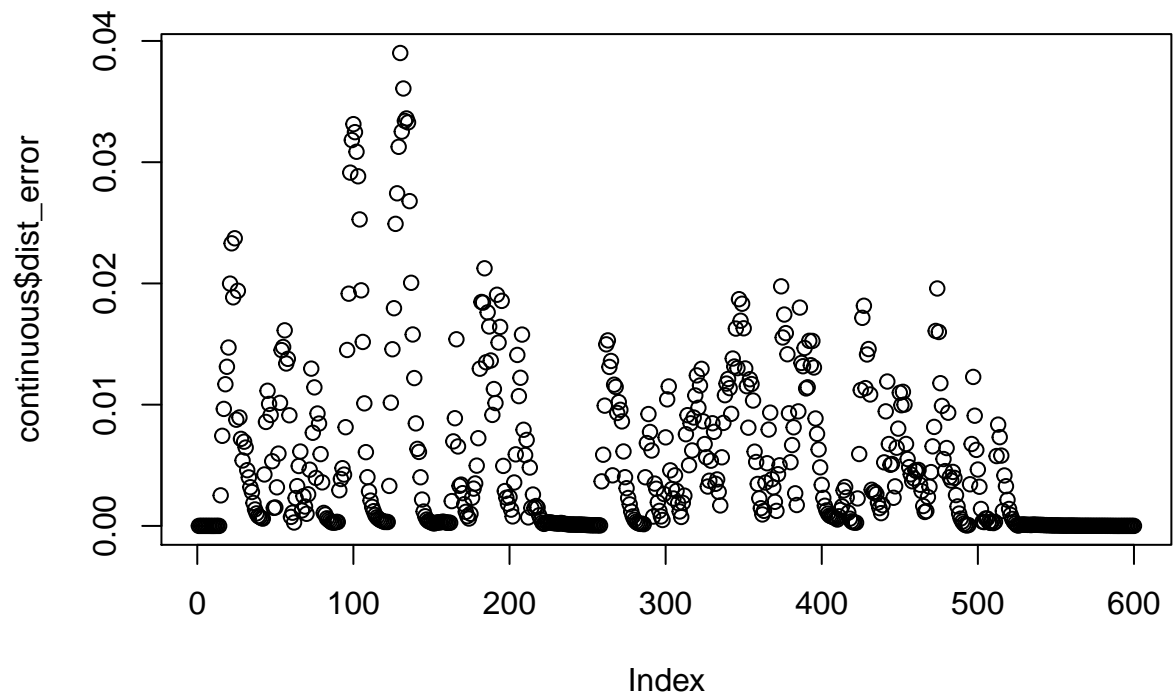
Continuous yaw error over time



Discrete yaw error over time



Continuous total distance error over time



Discrete total distance error over time

