two_stationary_noiseless Experiment Report

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This is a summary of the data from the two_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)
```

```
##      Min.   1st Qu.    Median      Mean   3rd Qu.      Max.
## 1.352e-05 2.067e-03 4.126e-03 4.119e-03 6.173e-03 8.219e-03
```

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

```
##       Min.    1st Qu.     Median       Mean    3rd Qu.       Max.
## -2.270e-10  1.845e-06  6.647e-06  8.590e-06  1.435e-05  2.645e-05
```

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

```
##       Min.    1st Qu.     Median       Mean    3rd Qu.       Max.
## -1.327e-05  1.596e-03  3.063e-03  3.024e-03  4.497e-03  6.114e-03
```

```
summary(continuous$horizontal_error)
```

```
##      Min.   1st Qu.    Median      Mean   3rd Qu.      Max.
## 1.352e-05 2.067e-03 4.126e-03 4.119e-03 6.173e-03 8.219e-03
```

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

```
##      Min.   1st Qu.    Median      Mean   3rd Qu.      Max.
## 7.610e-06 4.770e-05 8.962e-05 1.488e-02 3.025e-02 3.033e-02
```

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

```
##       Min.    1st Qu.     Median       Mean    3rd Qu.       Max.
## -8.177e-03 -5.771e-03  2.000e-09 -2.776e-03  1.110e-07  4.720e-07
```

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

```
##       Min.    1st Qu.     Median       Mean    3rd Qu.       Max.
## -5.100e-05  1.105e-05  3.047e-05  3.397e-05  5.354e-05  1.813e-04
```

```
summary(discrete$horizontal_error)
```

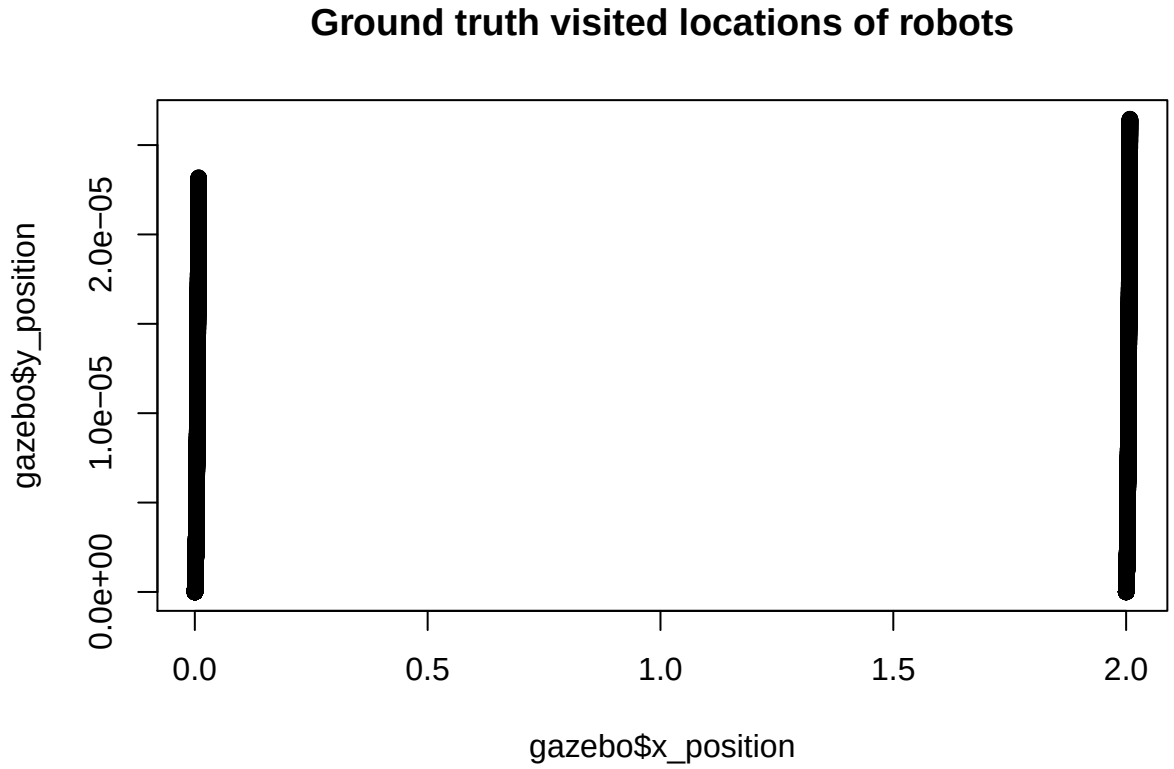
```
##      Min.   1st Qu.    Median      Mean   3rd Qu.      Max.
## 7.610e-06 4.770e-05 8.962e-05 1.516e-02 3.077e-02 3.140e-02
```

```
if (params$robot >= 2) {
    summary(external_data_averages)
}
```

```
##      Length Class  Mode
## [1,] 1      -none- numeric
## [2,] 1      -none- numeric
```

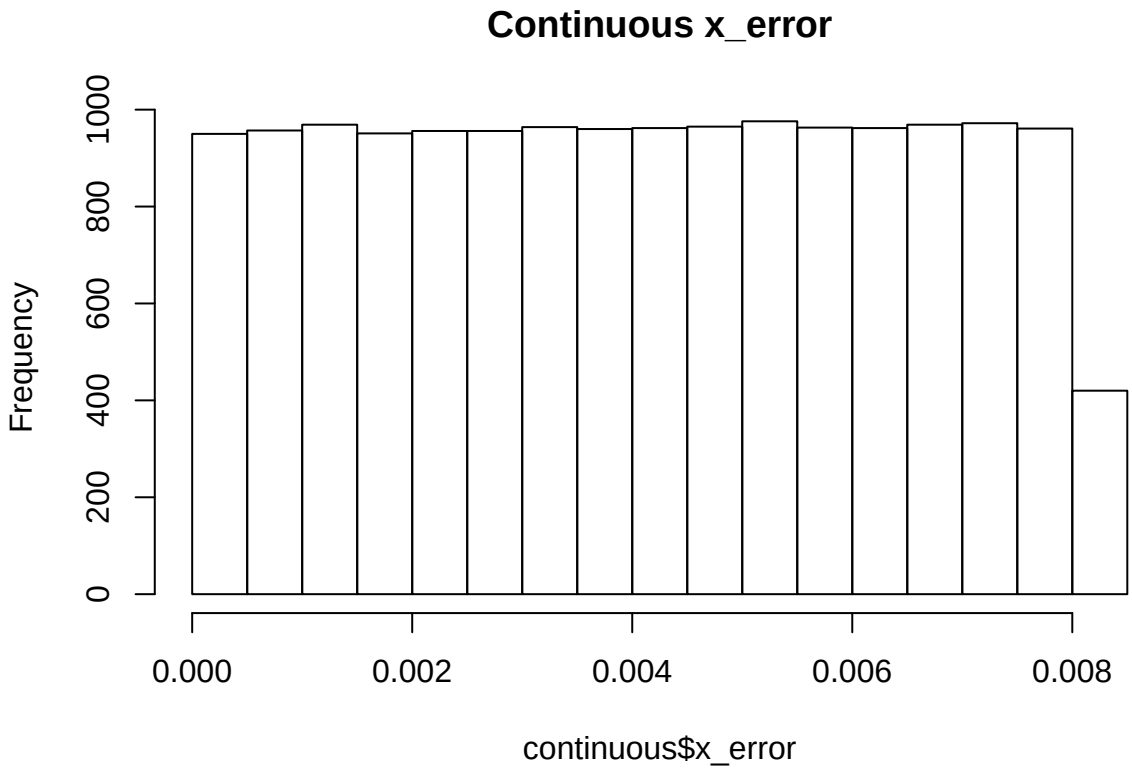
Shown below are plots representing the robot's motion and error over time.

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

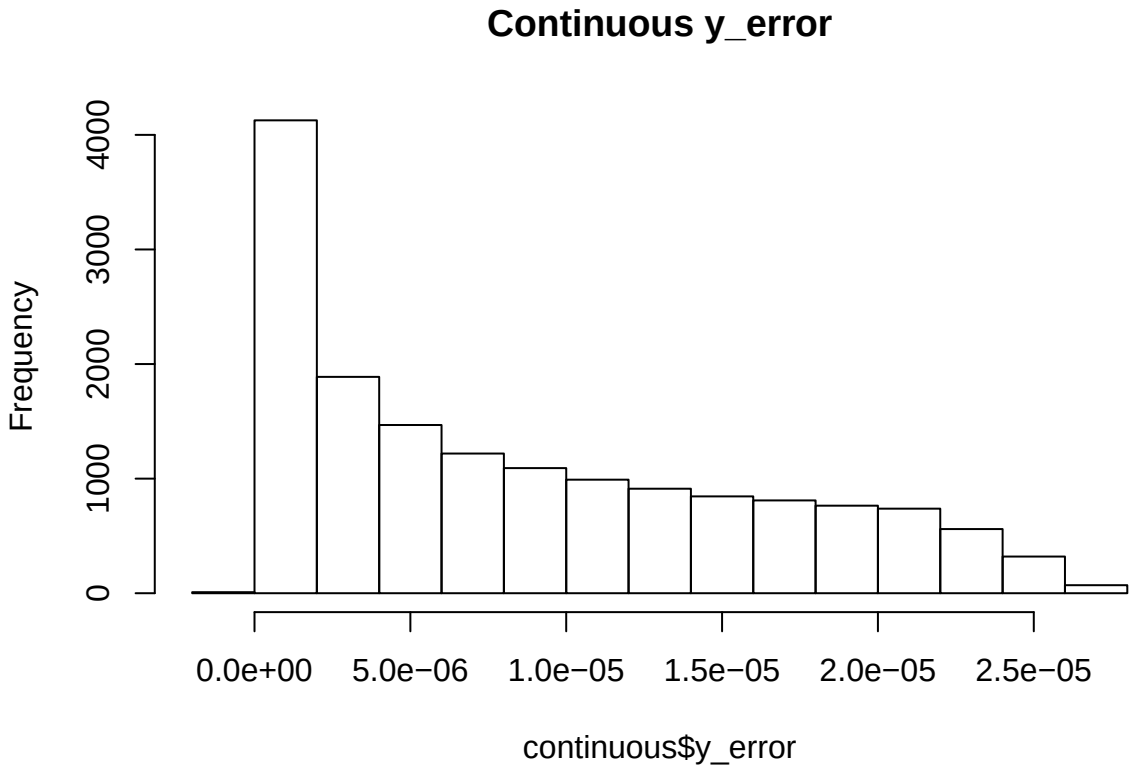



```r
hist(gazebo$dist_from_origin,
     main = "Distance from origin vs. time")
```

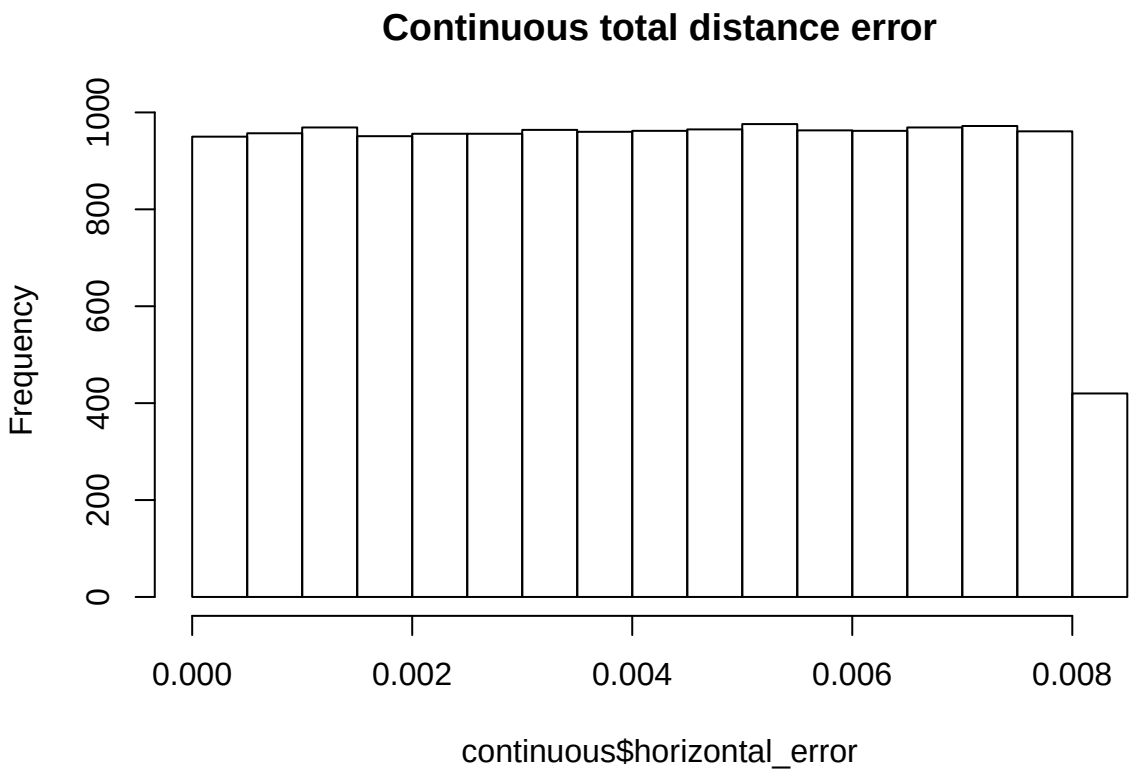
```r
hist(continuous$x_error,
     main = "Continuous x_error")
```



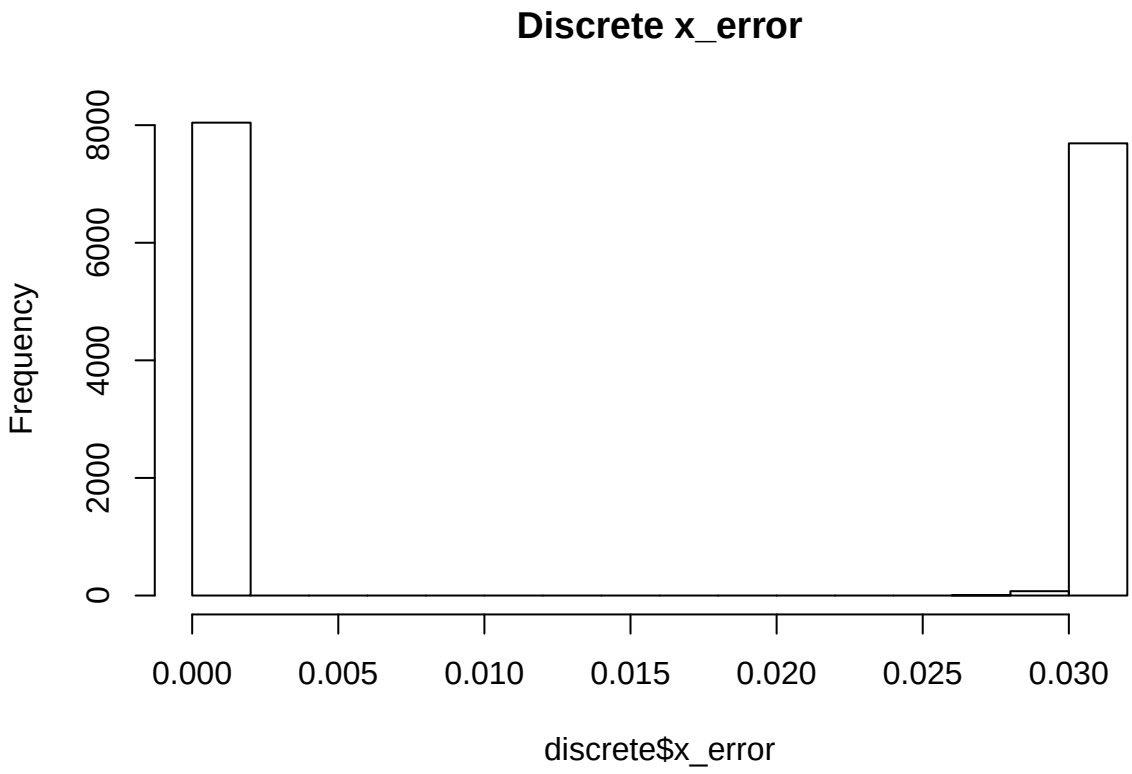

```r
hist(continuous$y_error,
      main = "Continuous y_error")
```



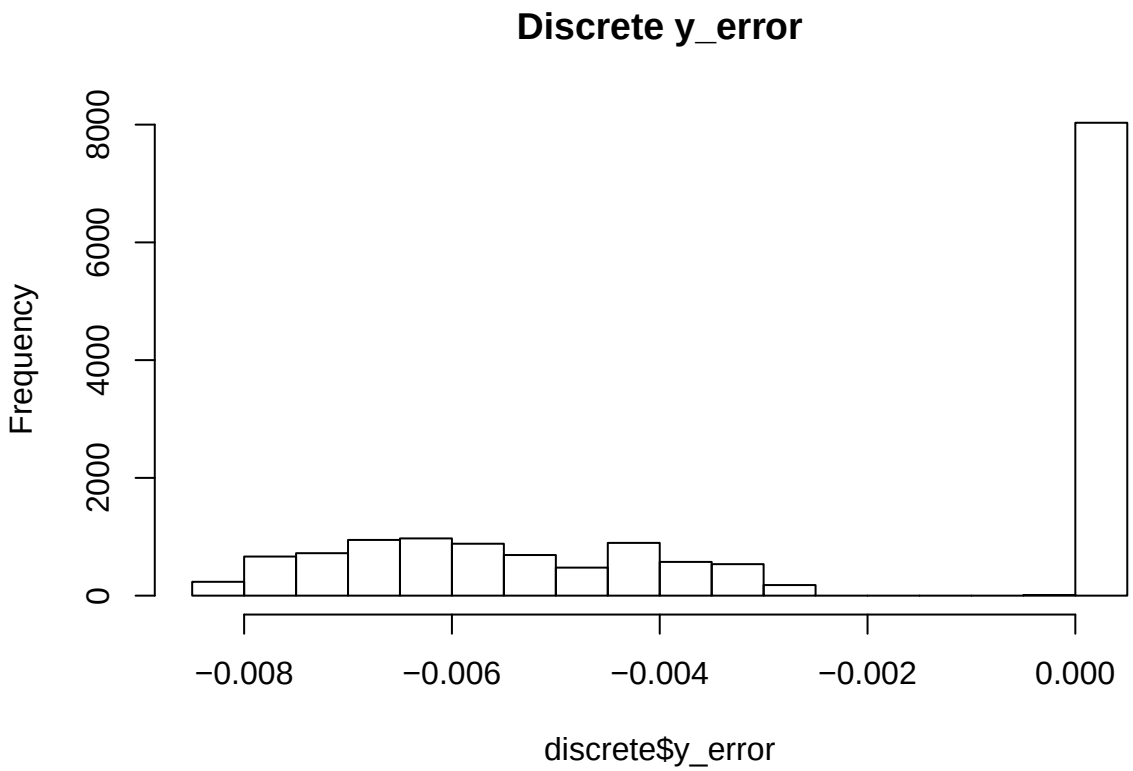
```r
hist(continuous$horizontal_error,
     main = "Continuous total distance error")
```



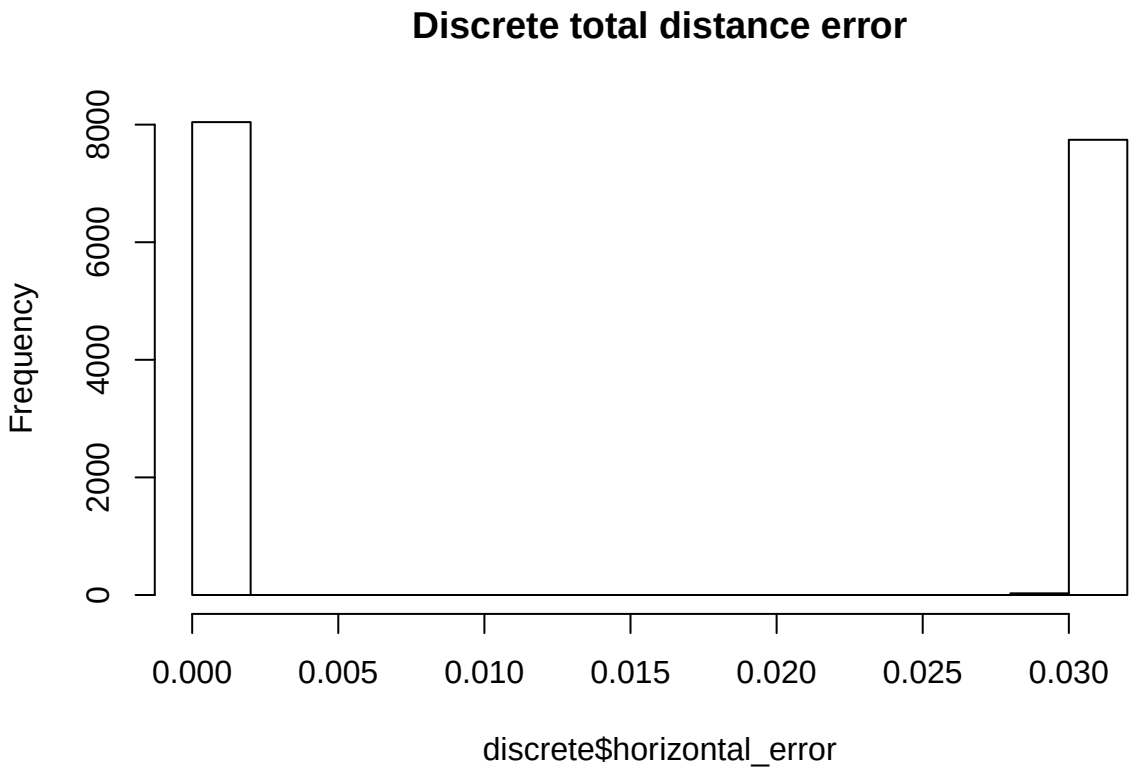

```r
hist(discrete$x_error,
     main = "Discrete x_error")
```



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




```r
hist (discrete$horizontal_error,
      main = "Discrete total distance error")
```



```
figure_dir <- "/home/matt/thesis/writing/r_figures/"
filename = paste0(figure_dir, params$experiment, "_continuous_error.pdf")
pdf(filename)
plot(continuous$horizontal_error, main="Continuous Filter Error", sub=paste0("For ", params$experiment,

dev.off()
```

```
## pdf
##   2
```

```
filename = paste0(figure_dir, params$experiment, "_discrete_error.pdf")
pdf(filename)
plot(discrete$horizontal_error, main="Discrete Filter Error", sub=paste0("For ", params$experiment, " E
dev.off()
```

```
## pdf
##   2
```

```
if (params$experiment == "one_stationary_noiseless") {
    gazebo$horizontal_error <- sqrt(gazebo$x_position ^ 2 + gazebo$y_position ^ 2)
    pdf(paste0(figure_dir, "gazebo_odom_drift.pdf"))

    plot(gazebo$horizontal_error, main="Gazebo Odometry Drift for Stationary Robot with Noiseless Odome
    dev.off()
}
```

```
table_dir <- "/home/matt/thesis/writing/autogenerated_tables/"

out_file <- paste0(table_dir, params$experiment, "_continuous_summary.tex")
tex_label <- paste0("tab:", params$experiment, "_continuous_summary")
stargazer(continuous,
          out=out_file,
          table.placement="h",
          label=tex_label,
          title=gsub("_", "-", paste0("Continuous Filter Estimate for ", params$experiment, " Experimen
          digits.extra = 20)
```

```
##
## % Table created by stargazer v.5.2 by Marek Hlavac, Harvard University. E-mail: hlavac at fas.harvar
## % Date and time: Mon, Aug 15, 2016 - 10:09:27 PM
## \begin{table}[h] \centering
##   \caption{Continuous Filter Estimate for two-stationary-noiseless Experiment}
##   \label{tab:two_stationary_noiseless_continuous_summary}
## \begin{tabular}{@{\extracolsep{5pt}}lccccc}
## \\[-1.8ex]\hline
## \hline \\[-1.8ex]
## Statistic & \multicolumn{1}{c}{N} & \multicolumn{1}{c}{Mean} & \multicolumn{1}{c}{St. Dev.} & \multi
## \hline \\[-1.8ex]
## x\_position & 15,813 & 0.983 & 1.000 & $-$0 & 2 \\
## y\_position & 15,813 & $-$0.000 & 0.000 & $-$0 & 0 \\
## yaw & 15,813 & 0.000 & 0.000 & $-$0 & 0 \\
## x\_variance & 15,813 & 44.971 & 25.891 & 0.127 & 89.805 \\
## y\_variance & 15,813 & 44.971 & 25.891 & 0.127 & 89.805 \\
## yaw\_variance & 15,813 & 40.510 & 23.326 & 0.115 & 80.888 \\
## yaw\_error & 15,813 & 0.003 & 0.002 & $-$0.00001 & 0.006 \\
## x\_error & 15,813 & 0.004 & 0.002 & 0.00001 & 0.008 \\
```

```
## y\_error & 15,813 & 0.00001 & 0.00001 & $-$0.000 & 0.00003 \\
## horizontal\_error & 15,813 & 0.004 & 0.002 & 0.00001 & 0.008 \\
## \hline \\[-1.8ex]
## \end{tabular}
## \end{table}
```

```
out_file <- paste0(table_dir, params$experiment, "_discrete_summary.tex")
tex_label <- paste0("tab:", params$experiment, "_discrete_summary")
stargazer(discrete,
          out=out_file,
          table.placement="h",
          label=tex_label,
          title=gsub("_", "-", paste0("Discrete Filter Estimate for ", params$experiment, " Experiment"))
          digits.extra = 20)
```

```
##
## % Table created by stargazer v.5.2 by Marek Hlavac, Harvard University. E-mail: hlavac at fas.harvard
## % Date and time: Mon, Aug 15, 2016 - 10:09:27 PM
## \begin{table}[h] \centering
##   \caption{Discrete Filter Estimate for two-stationary-noiseless Experiment}
##   \label{tab:two_stationary_noiseless_discrete_summary}
## \begin{tabular}{@{\extracolsep{5pt}}lccccc}
## \\[-1.8ex]\hline
## \hline \\[-1.8ex]
## Statistic & \multicolumn{1}{c}{N} & \multicolumn{1}{c}{Mean} & \multicolumn{1}{c}{St. Dev.} & \multic
## \hline \\[-1.8ex]
## x\_position & 15,813 & 0.972 & 0.985 & $-$0.000 & 1.980 \\
## y\_position & 15,813 & 0.003 & 0.003 & $-$0.000 & 0.008 \\
## yaw & 15,813 & 0.003 & 0.002 & $-$0.000 & 0.006 \\
## x\_variance & 15,813 & 0.321 & 0.363 & 0.002 & 1.099 \\
## y\_variance & 15,813 & 0.321 & 0.363 & 0.002 & 1.099 \\
## yaw\_variance & 15,813 & 0.501 & 0.242 & 0.091 & 0.926 \\
## x\_error & 15,813 & 0.015 & 0.015 & 0.00001 & 0.030 \\
## y\_error & 15,813 & $-$0.003 & 0.003 & $-$0.008 & 0.0000005 \\
## horizontal\_error & 15,813 & 0.015 & 0.015 & 0.00001 & 0.031 \\
## yaw\_error & 15,813 & 0.00003 & 0.00003 & $-$0.0001 & 0.0002 \\
## \hline \\[-1.8ex]
## \end{tabular}
## \end{table}
```

```
if (params$experiment == "one_stationary_noiseless") {
    stargazer(gazebo,
              out=paste0(table_dir, "gazebo_stationary_noiseless_summary.tex"),
              table.placement="h",
              label="tab:gazebo_stationary_noiseless_summary",
              title="Ground Truth Noiseless Odometry for Stationary Robot located at Origin",
              digits.extra = 20)
}
```