

# SLAM Assignment2: Kalman Filter

Dai ZiJia 2022233158

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## 1 Part A

### 1.1 Visualization of the trajectory of landmark observation

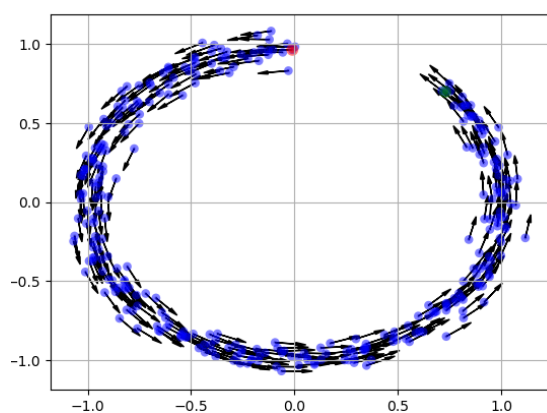


Figure 1: Visualization of the trajectory of landmark observation.

### 1.2 The trajectory concatenated by odometry measurement

### 1.3 The trajectory after apply the Kalman Filter

## 2 Part B

### 2.1 The trajectory of landmark observatio

### 2.2 The trajectory after apply the Kalman Filter

### 2.3 The robot's velocity over time (linear and angular)

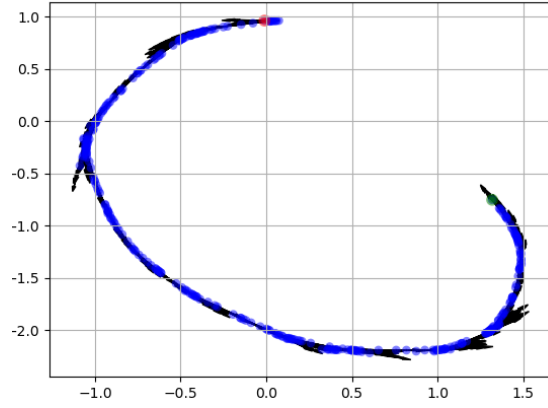


Figure 2: Visualization of the trajectory concatenated by odometry measurement.

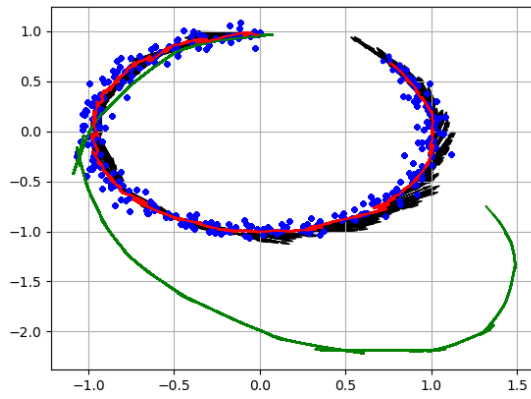


Figure 3: Visualization of the trajectory after apply the Kalman Filter. The red is predicted result.

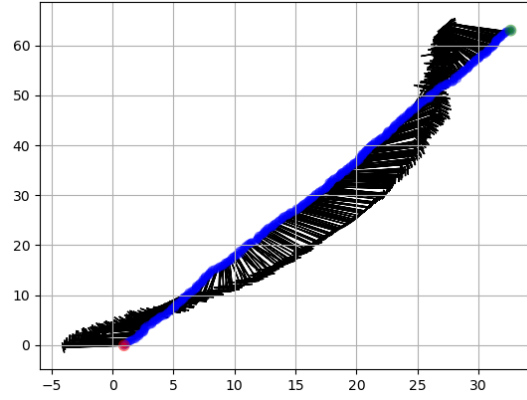


Figure 4: Visualization of the trajectory of landmark observation.

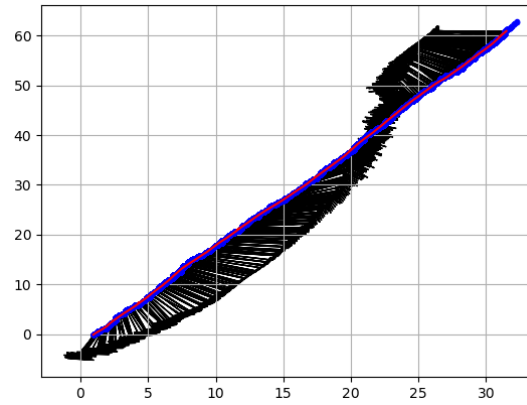


Figure 5: Visualization of the trajectory after apply the Kalman Filter.

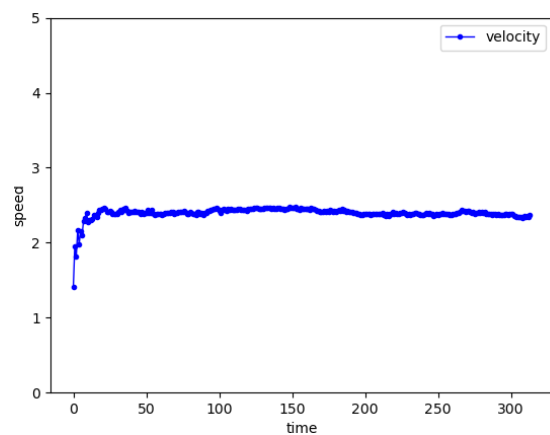


Figure 6: The robot's velocity over time (linear).

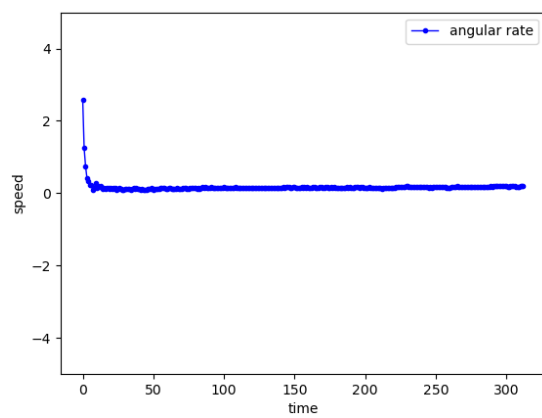


Figure 7: The robot's velocity over time (angular).