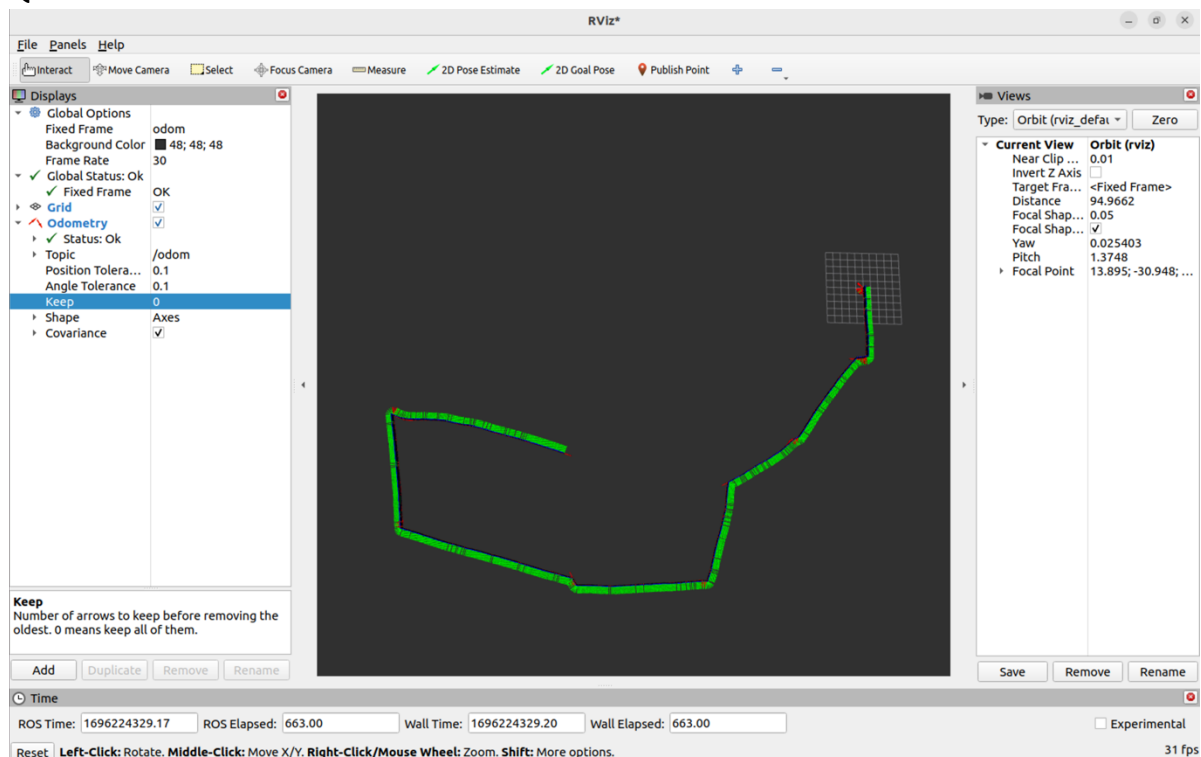


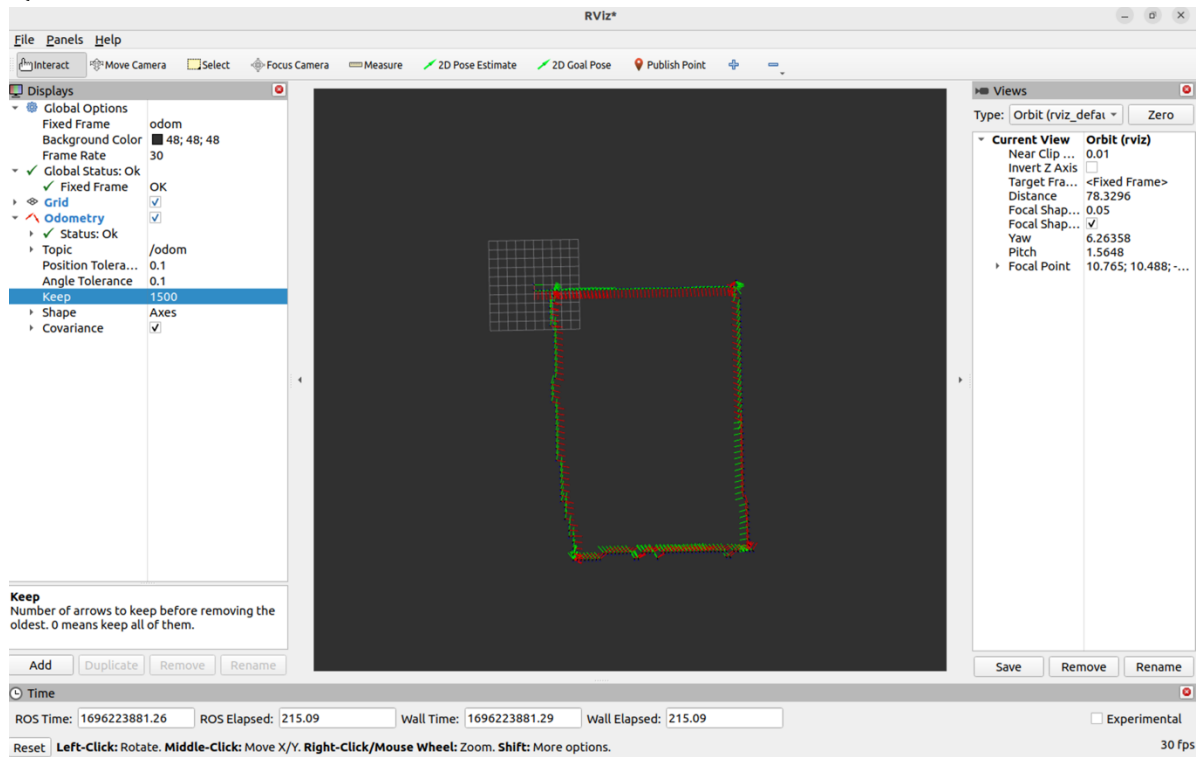
Question 1:

Topic	Message type	Publishing rate
Gyro_yaw	Float32	10
Accelx	Float32	10
Accely	Float32	10
Accelz	Float32	10
Blspeed	Float32	10
Brspeed	Float32	10
Flspeed	Float32	10
Frspeed	Float32	10
Gyro_pitch	Float32	10
Gyro_roll	Float32	10
latitude	Float32	10
longitude	Float32	10
Parameter_events	ParameterEvent	10
Rosout	Log	10

Question 2:



Question 3:



Question 4:

In part1 there is a direct calculation of the robot's position using differential drive kinematics and Euler's integration. In part2 the position is determined using the GPS-to-Cartesian conversion. The direct calculation of robot position in part1 led to an improper path/trajectory of the robot while the implementation of GPS measurements provided a rectangular, organized path/trajectory of the robot.