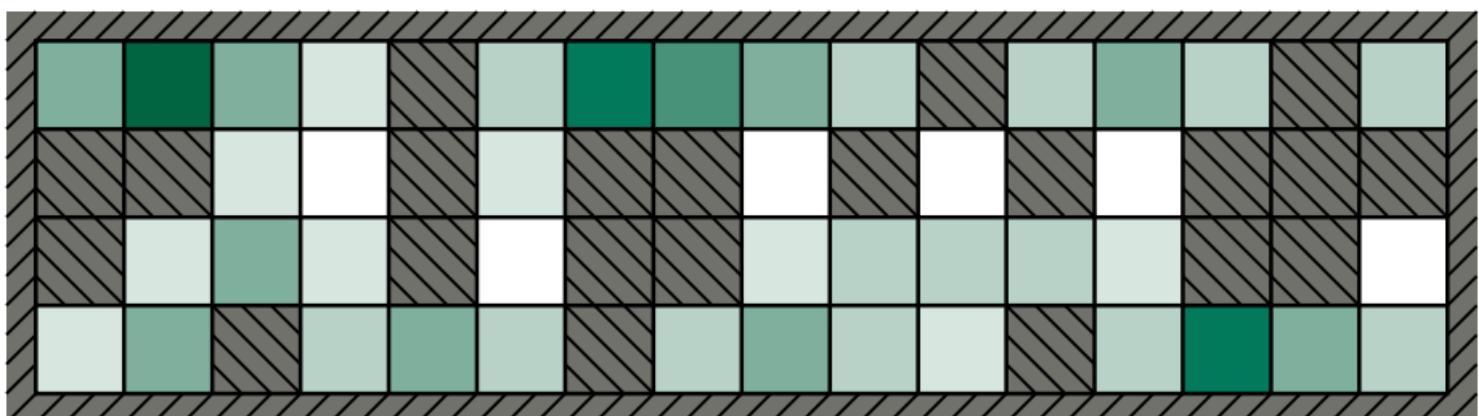


(a) Posterior distribution over robot location after $E_1 = 1011$



(b) Posterior distribution over robot location after $E_1 = 1011, E_2 = 1010$