Thank you for reviewing my thesis, I have followed the recommendations and, I have explained them in the same sequence in which these were recommended.

1. Few acronyms were not defined properly, which are properly defined now. The acronyms which I added before their use, in the corrected file, are mentioned below

A) PC/BC-DIM

B) Wi-Fi

C) USBL

D) SONAR

E) SLAM

F) B-PR-F

G) RMS

2. The mentioned figures 4.1, 4.2, 4.3 4.4, 4.5, 4.7 4.8, 4.9, 4.10 4.11 are now corrected with labels as instructed. Other than mentioned figures I added labels to figure 2.4, 3.2, 3.3, 3.4, 3.5, 3.6. I hope now all figures can be followed.

3. I have already compered particle filter. Monte Carlo Localization (MCL) is also known as Particle Filter localization and In table 4.4 I have compared MCL. Other than it I have mentioned “(using Particle Filter)” now.

4. I discussed it with my supervisor the name "Robot Localization". In this task, we are interested in finding the location of robot so “Robot Localization” is more dominant than “Robot tracking” in our point of view.