Week4

In Part A
There is **node** named **myodomtry** which is initialized **publishes** a **Twist** message of **linear velocity 0.11** and **angular velocity 0.8** with a **Rate of 5** to **/odometry_tracker**

In Part B
There is **node** named **myOdometry** which is initialized **publishes** a **Twist** message of **linear velocity 0.083333** and **angular velocity 0** with a **Rate of 5** to **/odometry_tracker** for total **9 iteration** and then stop the loop. Its **subscribed** to **/odom** to give the pose and to find the distance between two points

In Part C
There is **node** named **myOdometry** which is initialized **publishes** a **Twist** message of **linear velocity 0.083333** and **angular velocity 0** with a **Rate of 5** to **/odometry_tracker** for total **9 iteration.** Its **subscribed** to **/odom** to give the pose ,I tried to setup the task but I think there were few bugs due to which I wasn't able to do it and perform it you can check the code.

Week5

PartA,PartB, PartC Combine
There is **node** named **controller_node** which is initialized **publishes** a **Twist message** based on the conditions. Its **subscribed** to **/trilateration_data** and **/odom.** Later I have applied the **EKF** but due to some bug its not running perfectly. **Rate** is set to **5.** Due to some bug the matrix H was also not getting printed out