Simultaneous Localization and Mapping (SLAM) Assignment - Particle Filters

40575042H Jacky Wang

Discuss the results. Were the results expected or did they surprise you?

These turned out to be bad results because the particles' location is not what I predicted. Also, I cannot predict their location for they are all random. I think the reason I failed is because I didn't provide comprehensive code.


Did the results highlight shortcomings in the system? Do you have any ideas for how to fix those?

I think that resampling function is very important part in the whole system, if I didn't chose the right way to resample particles, it will always chose the top10 or 30 in all of particles, so I think that resampling function is the reason why I failed in this assignment.
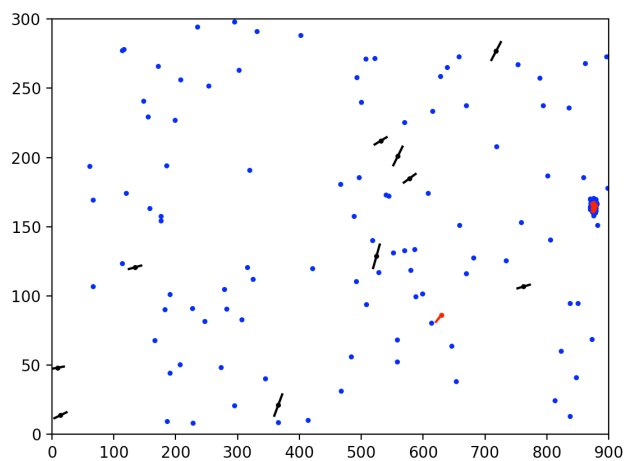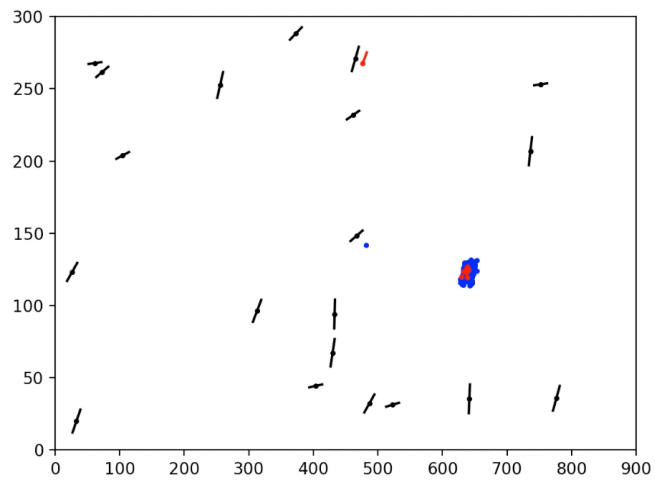
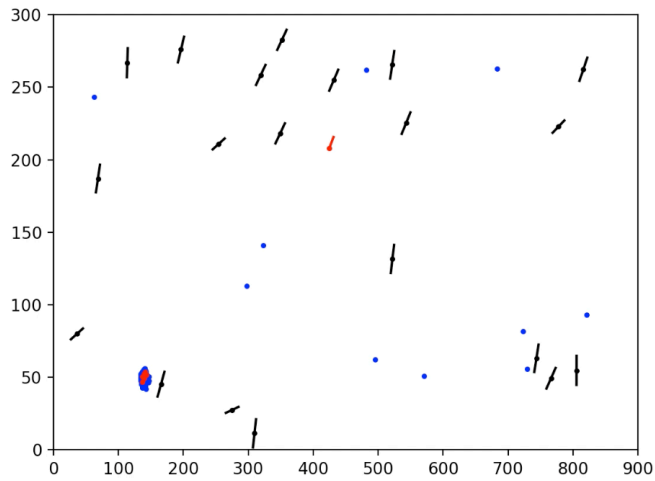## obstacles:10, particles: 10
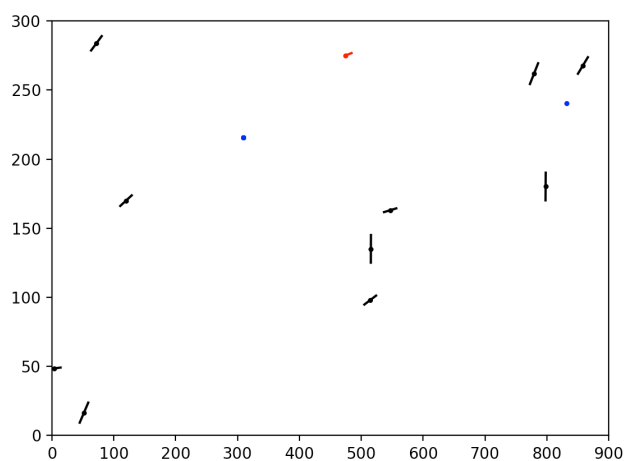
obstacles:10, particles: 100
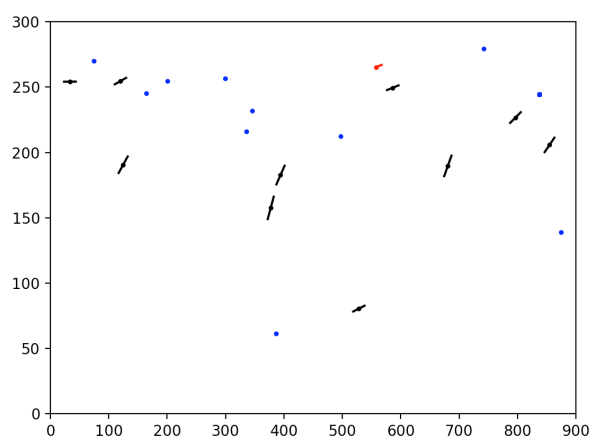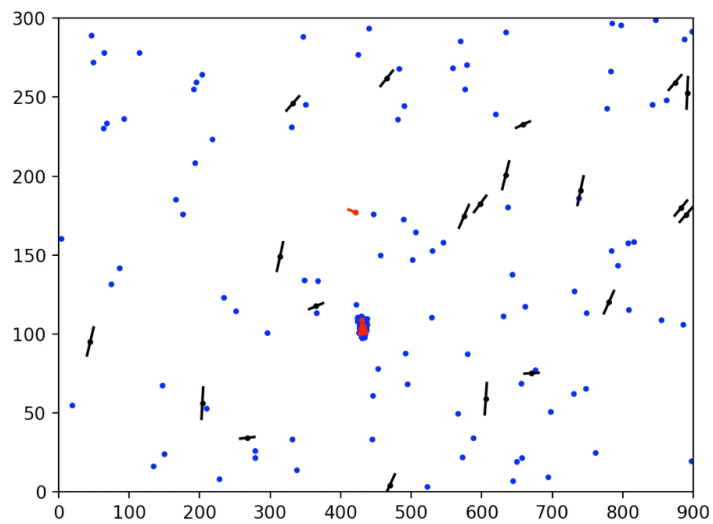

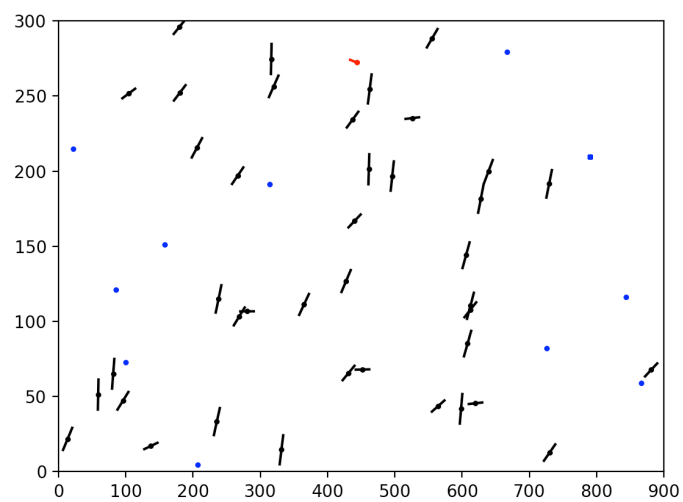## obstacles:10, particles: 1000

obstacles:20, particles: 10
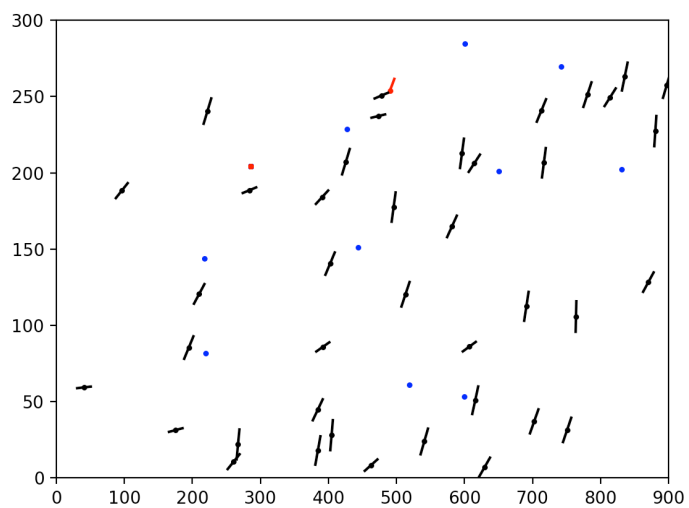

obstacles:20, particles: 100

obstacles:20, particles: 1000

obstacles:40, particles: 10

obstacles:40, particles: 100

obstacles:40, particles: 1000