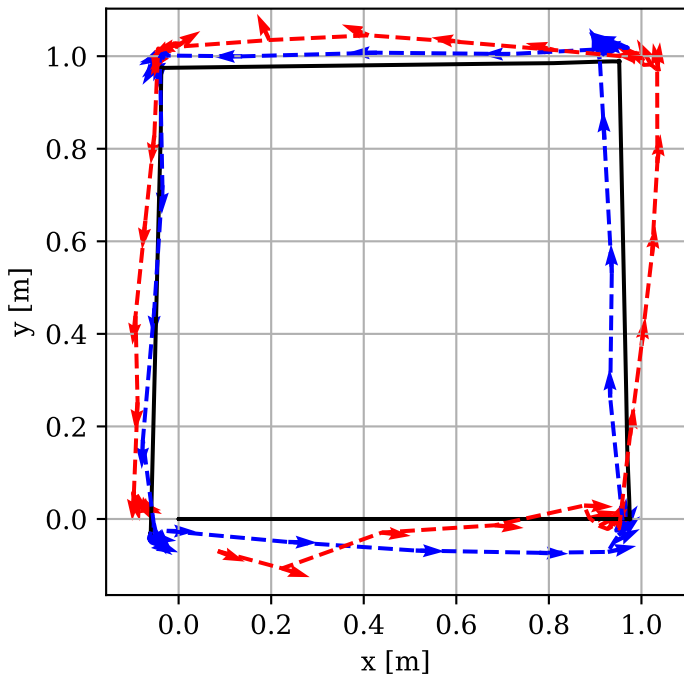
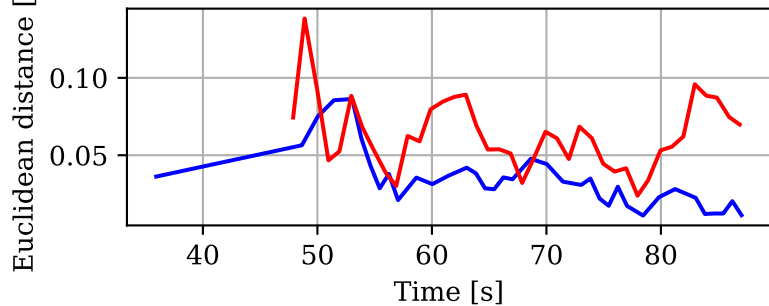


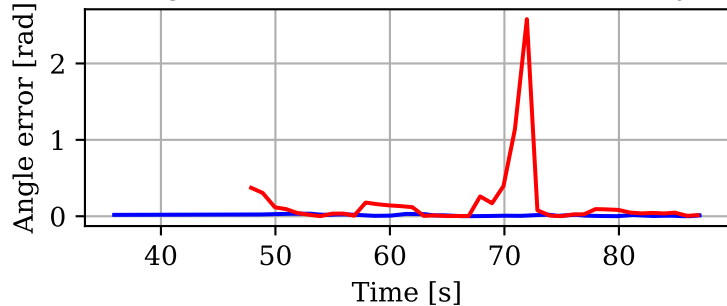
Trajectory comparison



Euclidean distance to Odometry



Angle error compared to Odometry



— Odometry — Particle estimation stack — Particle estimation own