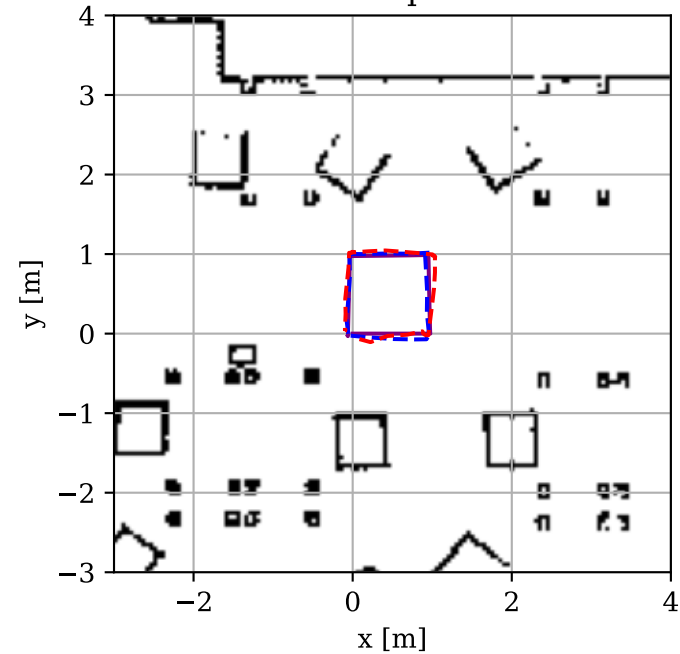
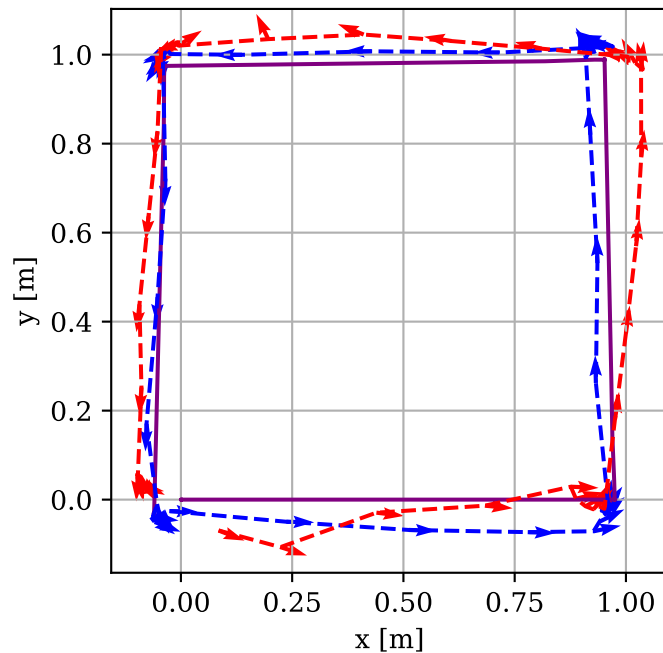


Path comparison

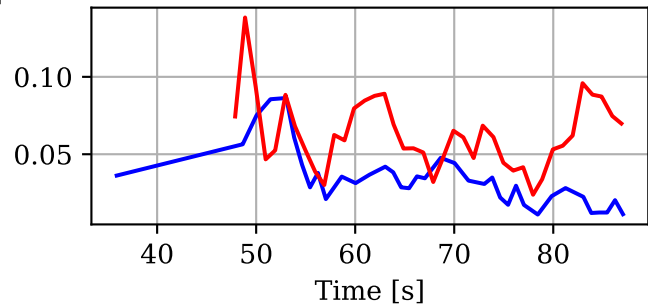


Path comparison



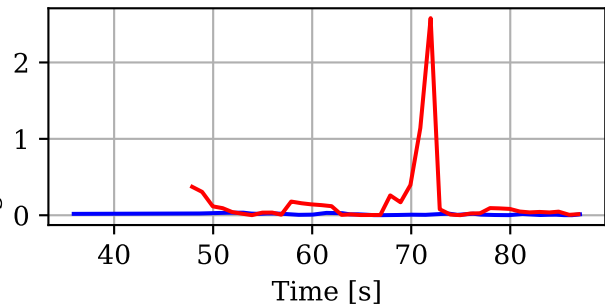
Euclidean distance [m]

Euclidean distance to Odometry



Angular error [rad]

Angular error compared to Odometry



— Odometry    — Particle estimation stack    — Particle estimation own