

two_mobile_noiseless Turtlebot 1 Report

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This is a summary of the data from the two_mobile_noiseless experiment, Turtlebot #1.

The runtime of this experiment was 0 hours, 25 minutes, and 9.8 seconds.

The total number of external pose measurements received by the robot during this time was 1303 which means poses were received at an average of 0.8630282 poses per second.

Shown below is the summary of each filter's error for both x and y coordinates, and also the error in total distance.

```
summary(continuous$x_error)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## -9.1740  0.2817  6.5180  3.2490  6.5190 11.9100

summary(continuous$y_error)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## -19.200 -15.630 -3.839  -6.372   1.033   6.882

summary(continuous$yaw_error)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## -3.14100 -1.58200 -0.02786 -0.01089  1.56700  3.14100

summary(continuous$dist_error)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## 0.000016  6.236000  9.309000 10.840000 16.940000 19.290000

summary(discrete$x_error)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## -7.502000 -0.023620  0.006108  0.021940  0.292000  4.014000

summary(discrete$y_error)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## -3.429000 -0.093500  0.000143  0.138700  0.239600  3.640000

summary(discrete$yaw_error)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## -3.141000 -1.316000 -0.039910 -0.003839  1.385000  3.140000

summary(discrete$dist_error)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## 0.000000  0.03103  0.31660  0.71930  0.89660  8.30100

summary(noisy_odom$x_err)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## -13.250  -4.110  -2.860  -2.555  -0.756   6.232
```

```

summary(noisy_odom$y_err)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## -5.179 -1.128  1.373   1.995  4.148 13.690

summary(noisy_odom$dist_err)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## 0.000041 3.287000 4.837000 5.244000 6.112000 15.450000

if (NROW(gps) > 0) {
  summary(gps$x_err)
  summary(gps$y_err)
  summary(gps$dist_err)
}

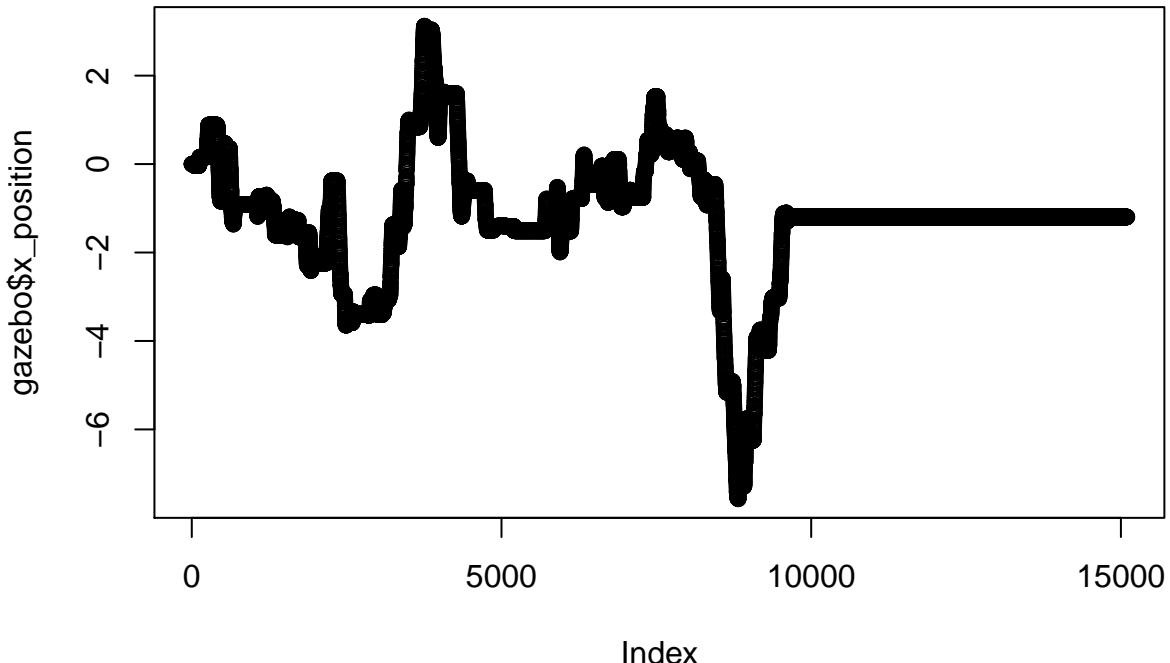
##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## 0.03831 1.37900 2.66500 2.71600 3.94500 7.83300

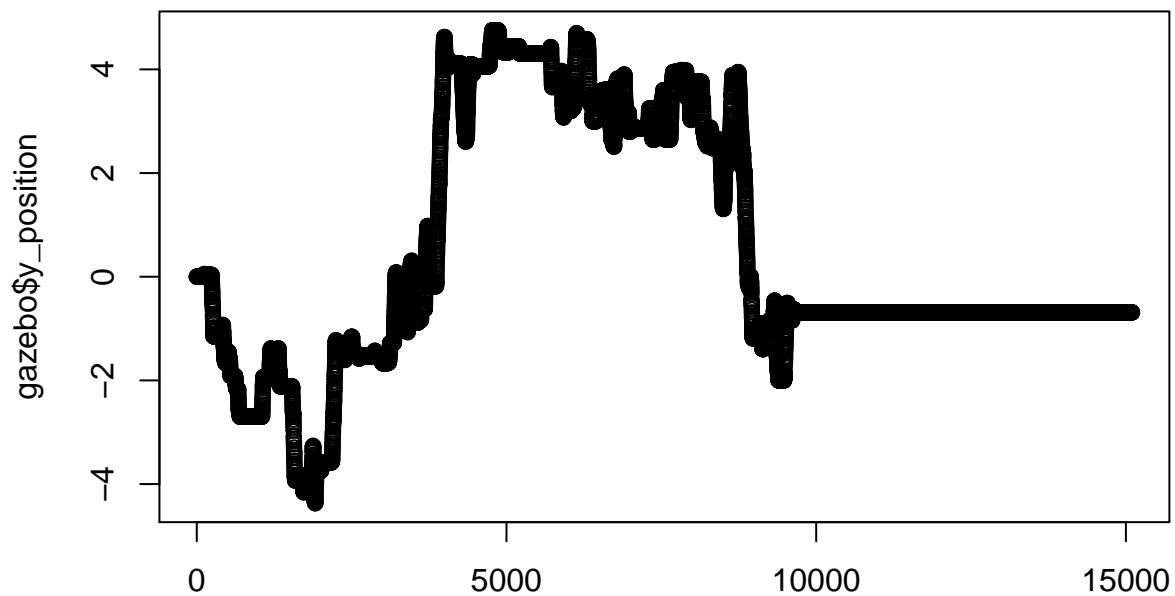
if (NROW(noisy_odom) > 0) {
  summary(noisy_odom$x_variance)
  summary(noisy_odom$y_variance)
  summary(noisy_odom$yaw_variance)
}

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## 0.000e+00 2.642e-06 7.443e-06 3.437e-03 7.549e-03 8.887e-03

```

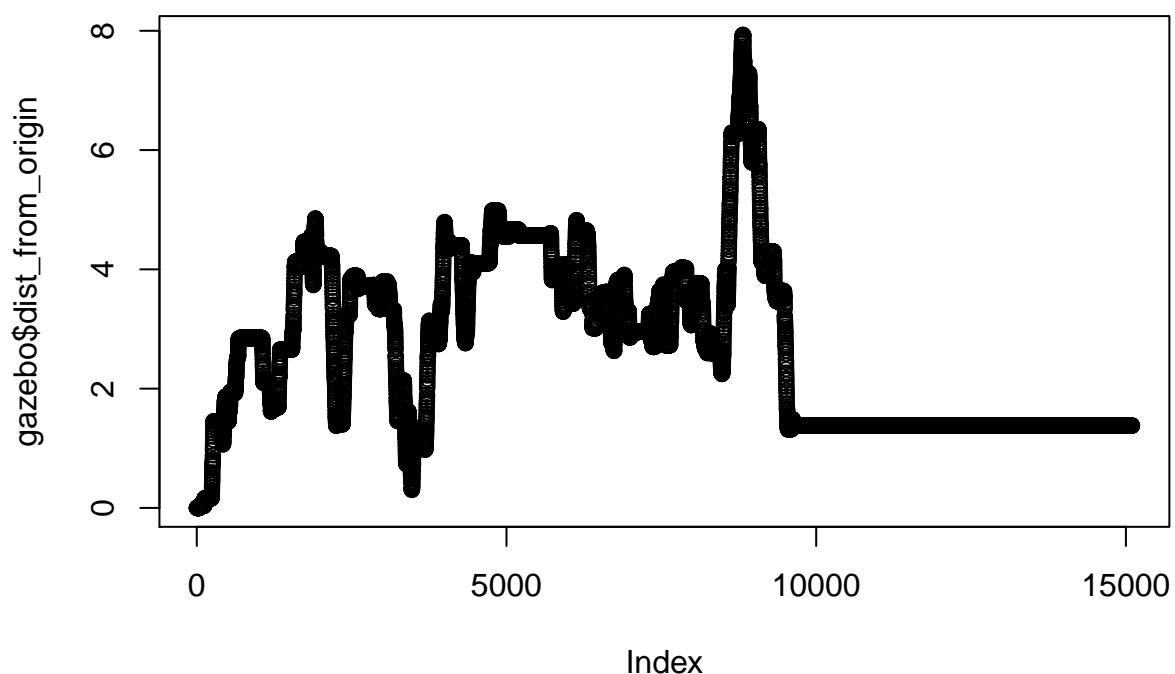
X coordinate of robot over time



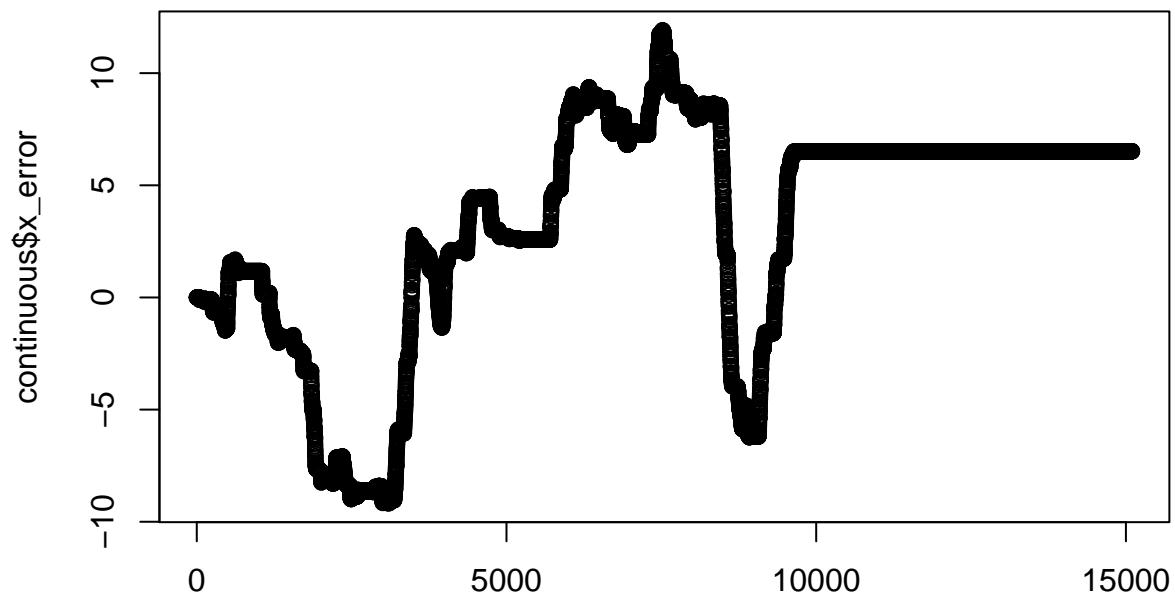


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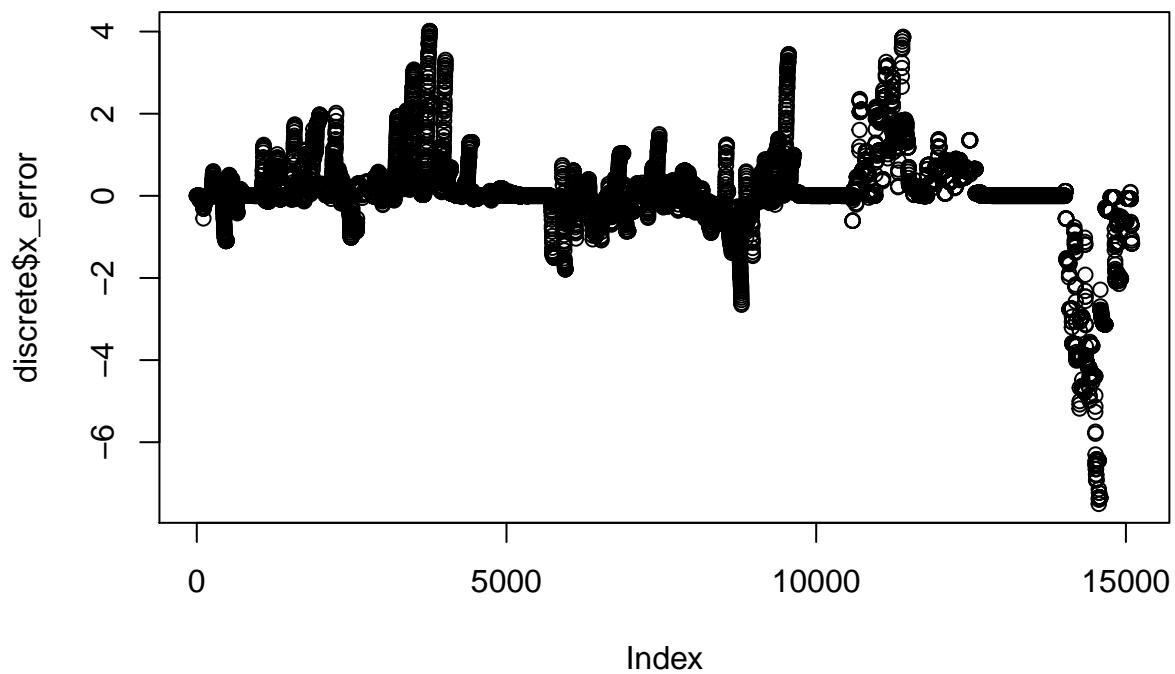
Distance from origin vs. time



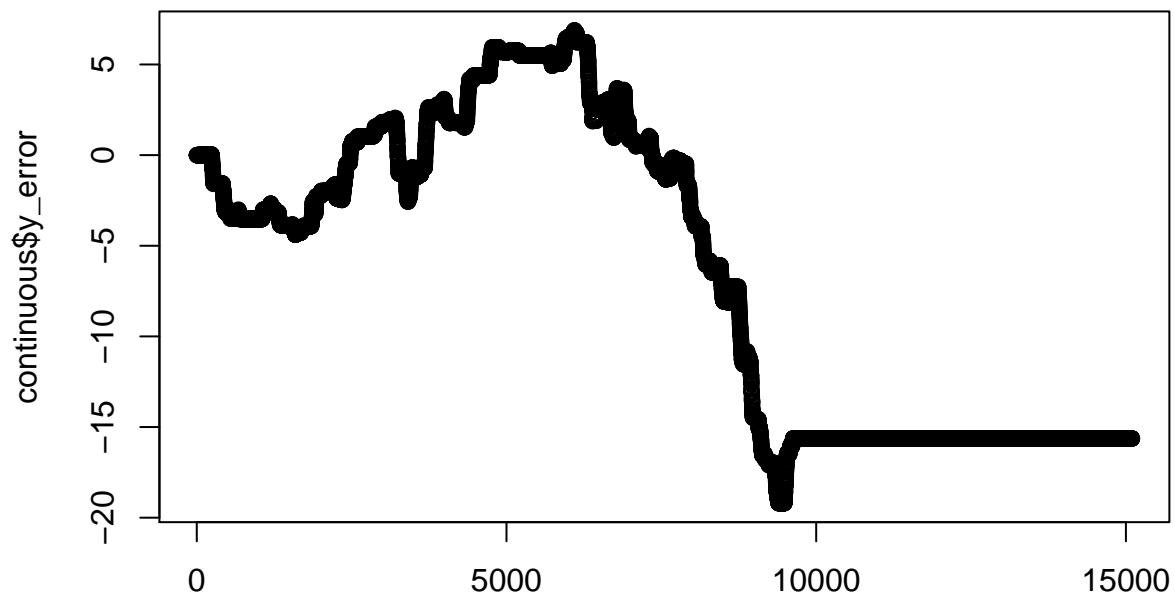
Continuous x_error over time



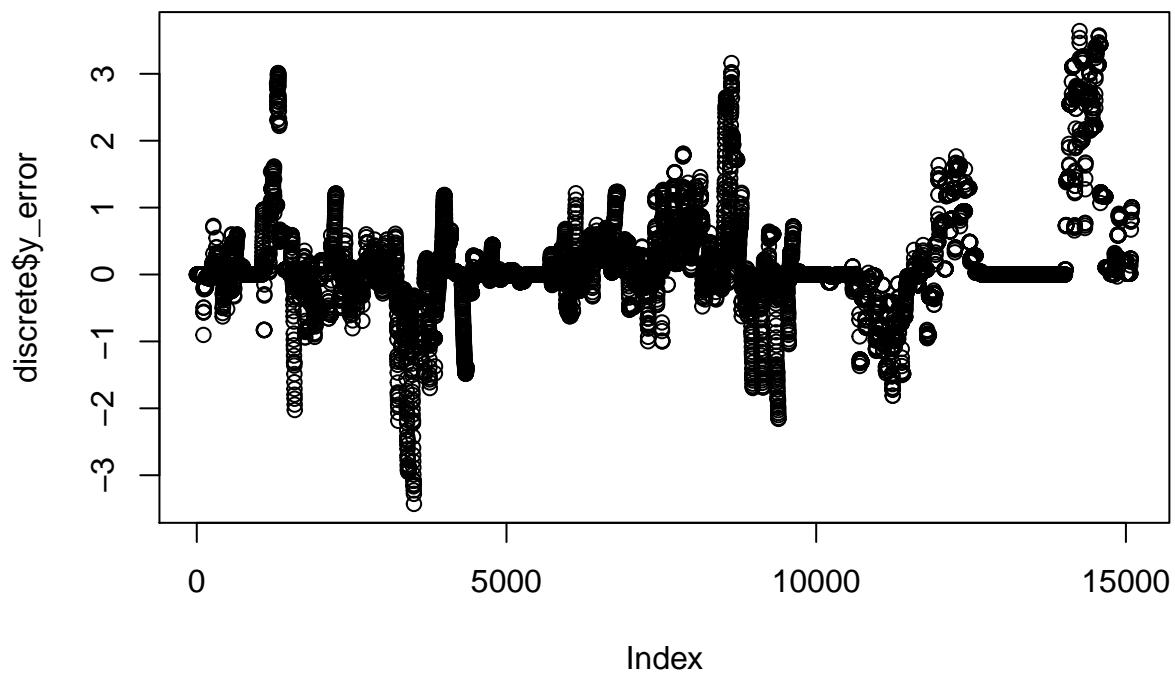
Discrete x_error over time



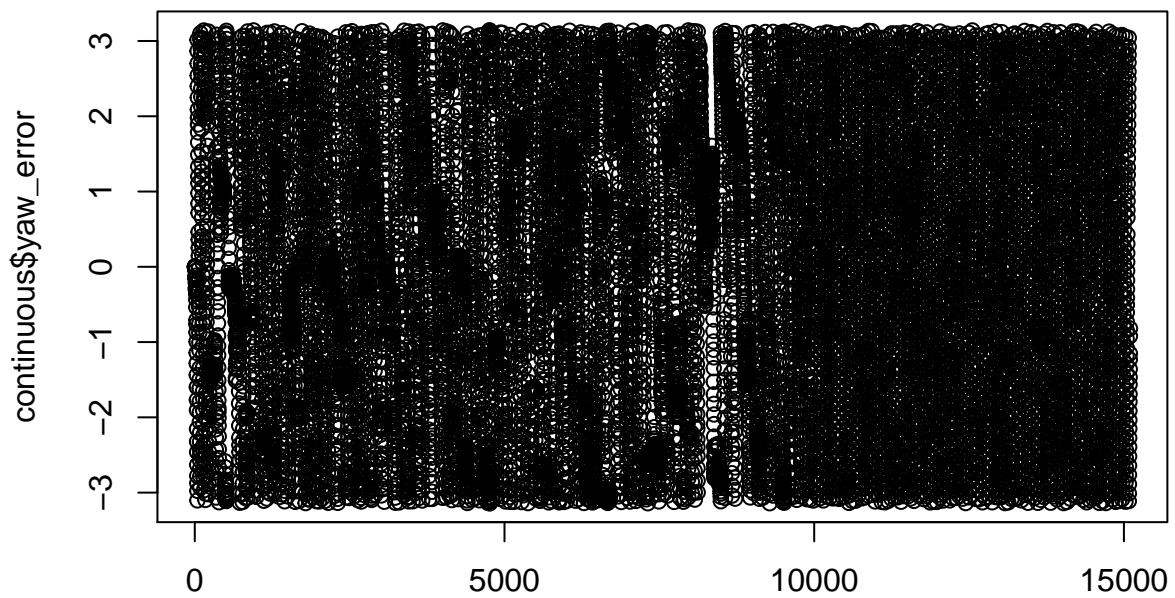
Continuous y_error over time



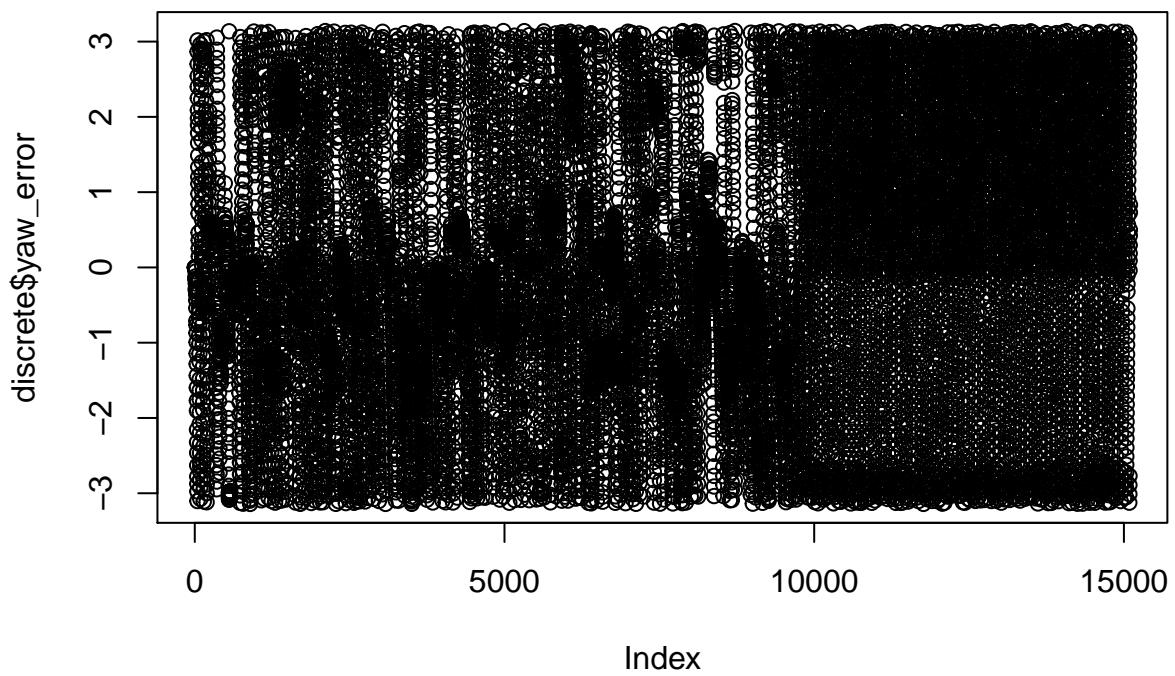
Discrete y_error over time



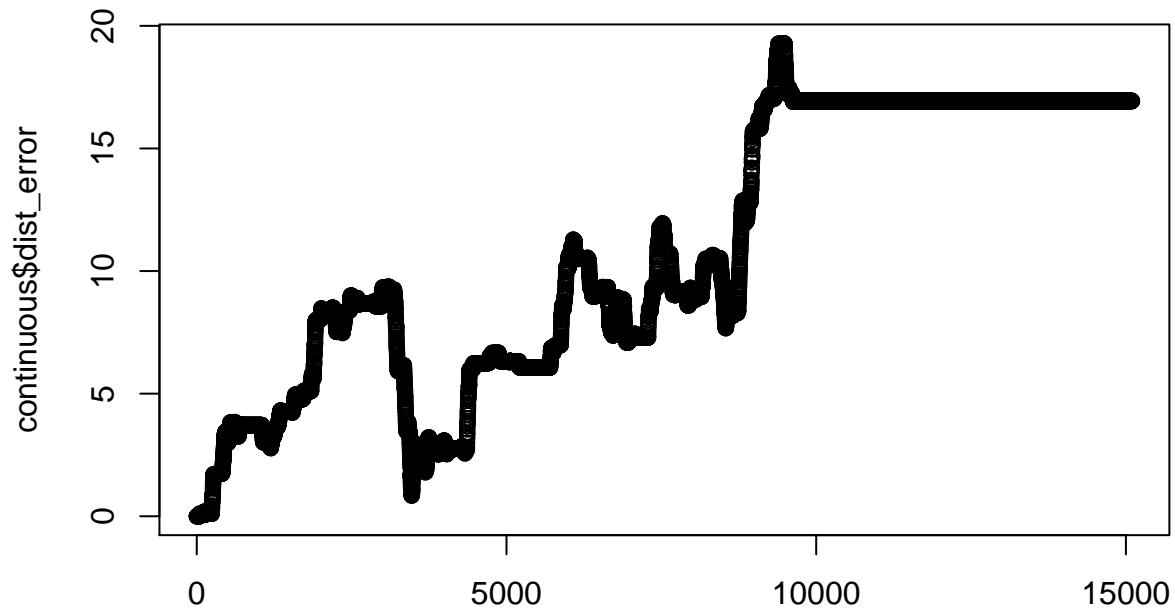
Continuous yaw error over time



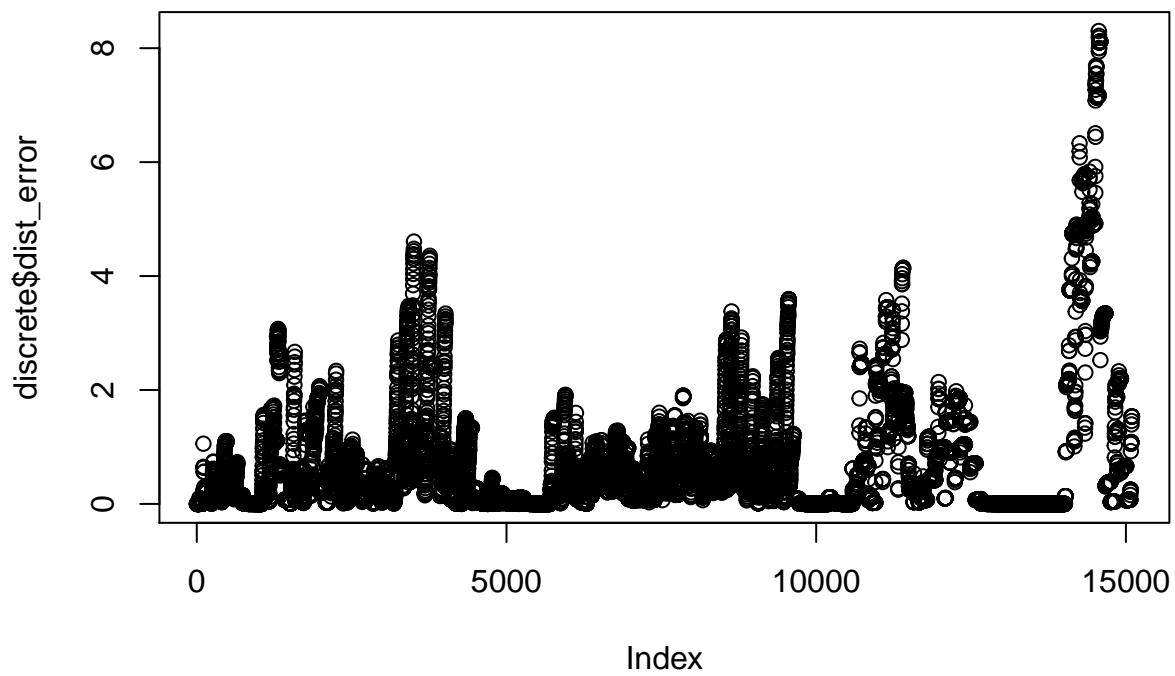
Discrete yaw error over time



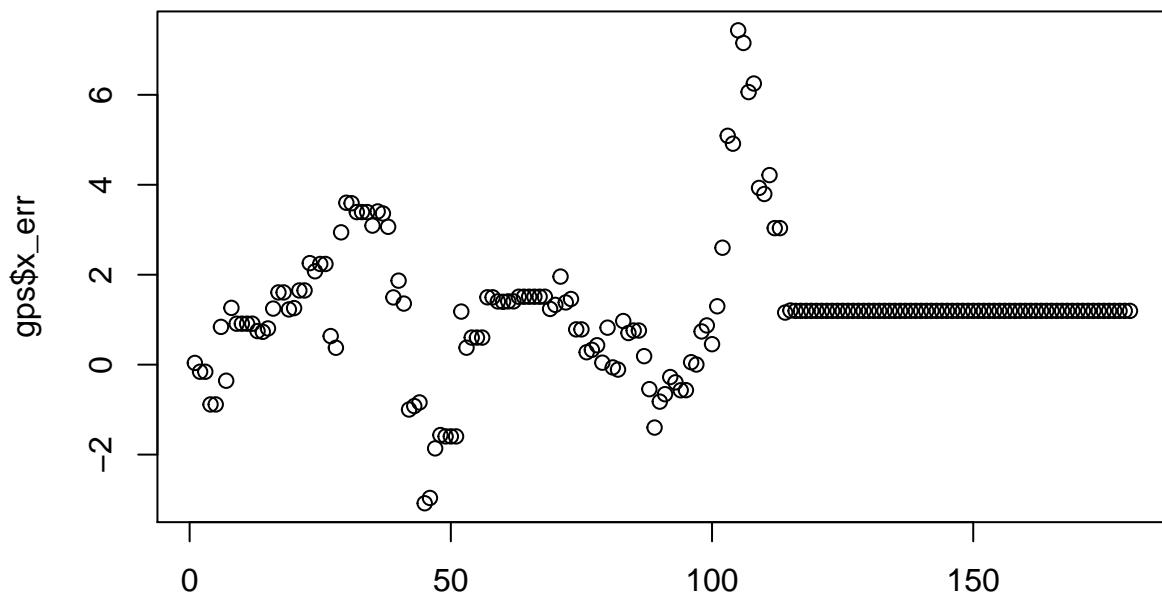
Continuous total distance error over time



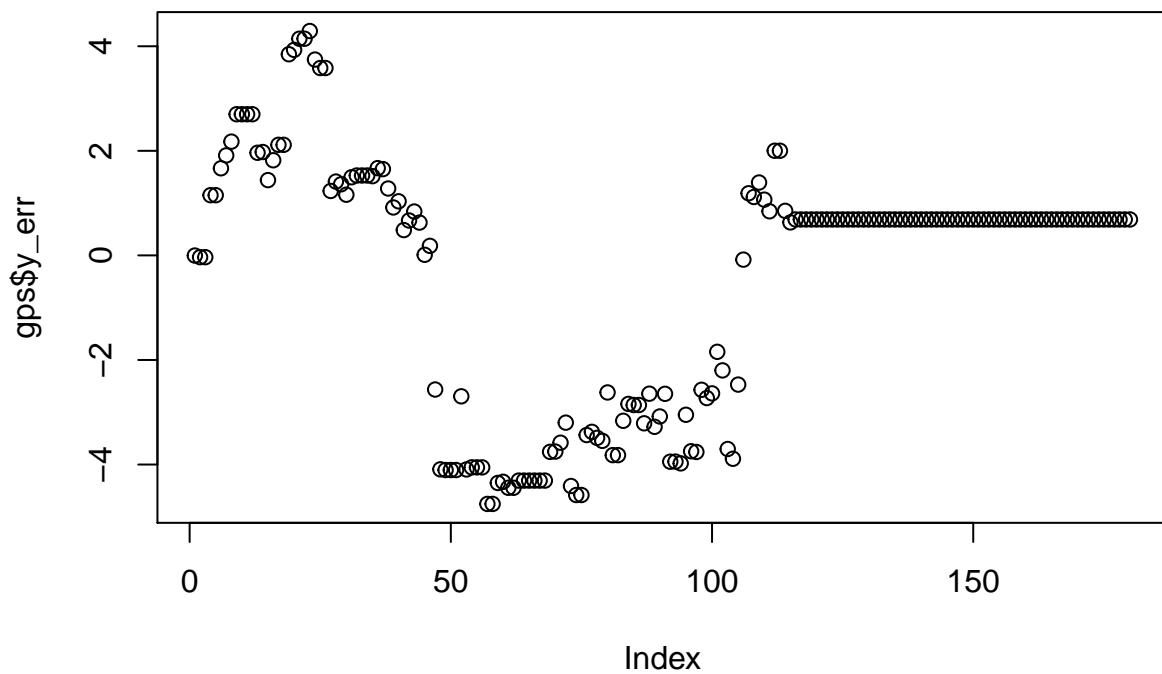
Discrete total distance error over time



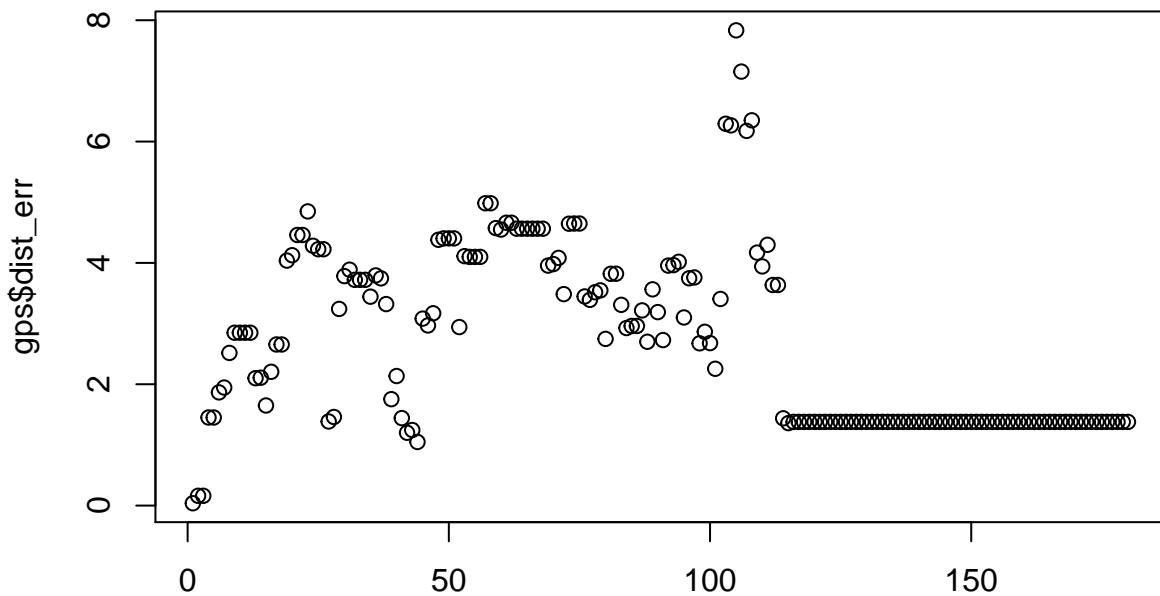
GPS X Error Over Time



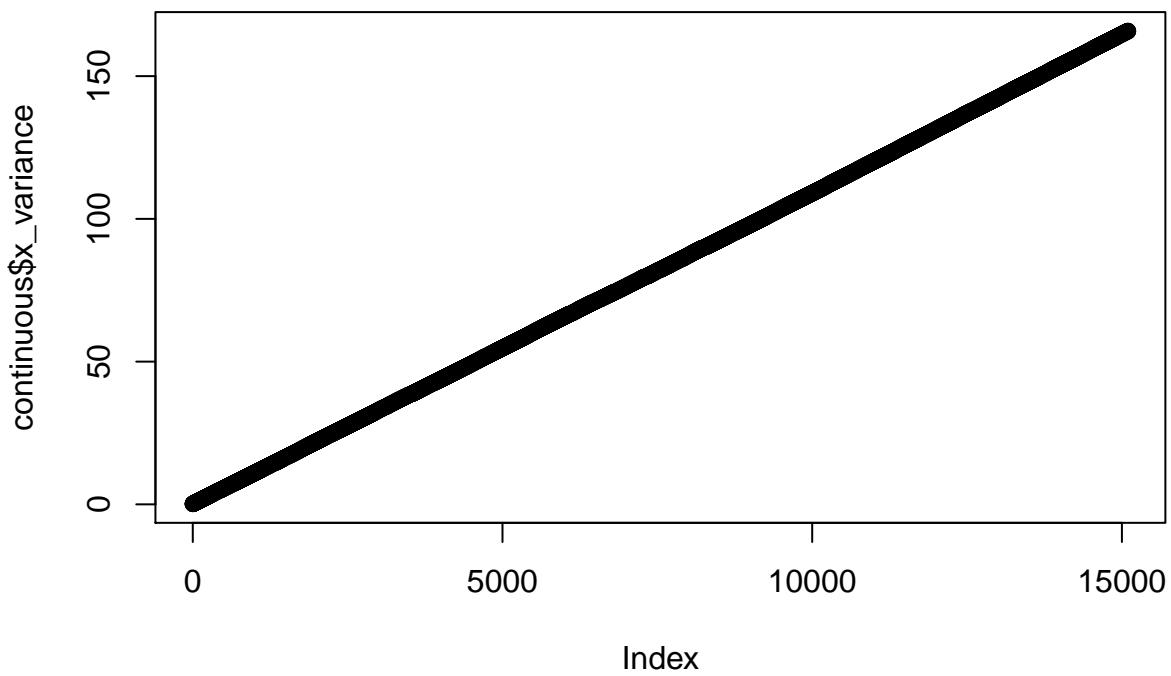
GPS Y Error Over Time



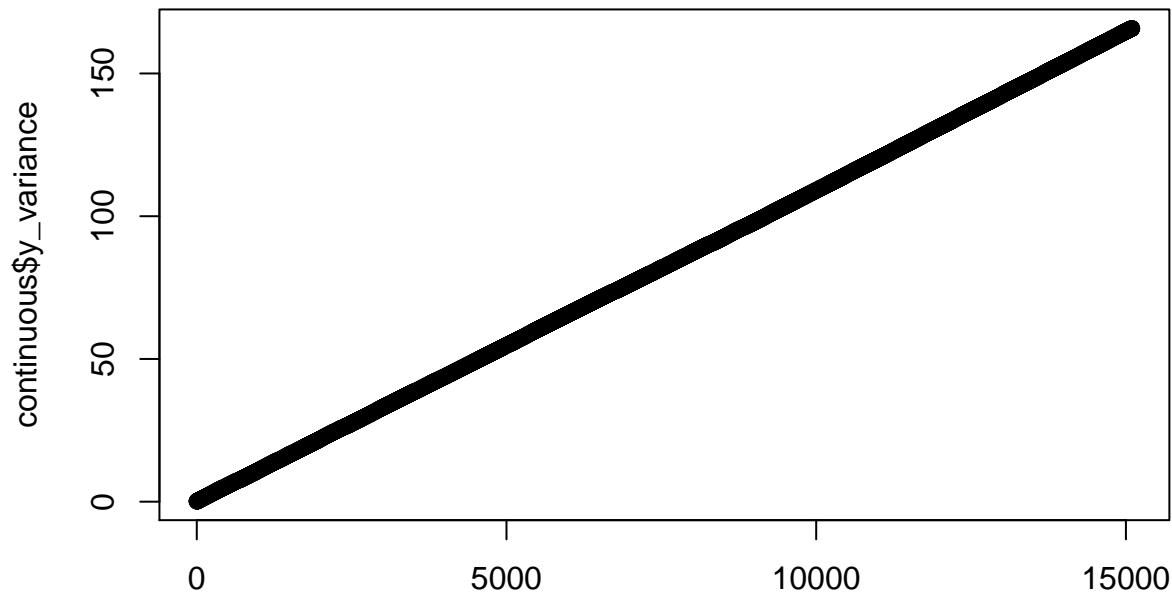
GPS Horizontal Distance Error Over Time



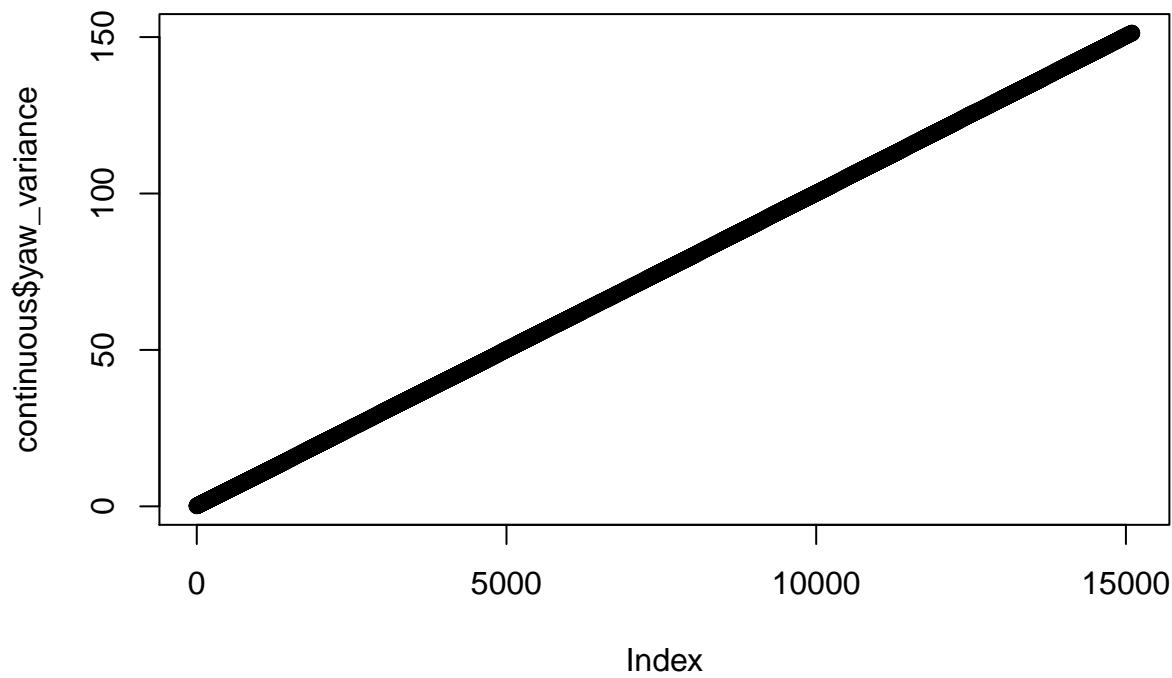
Continuous Filter X Variance Over Time



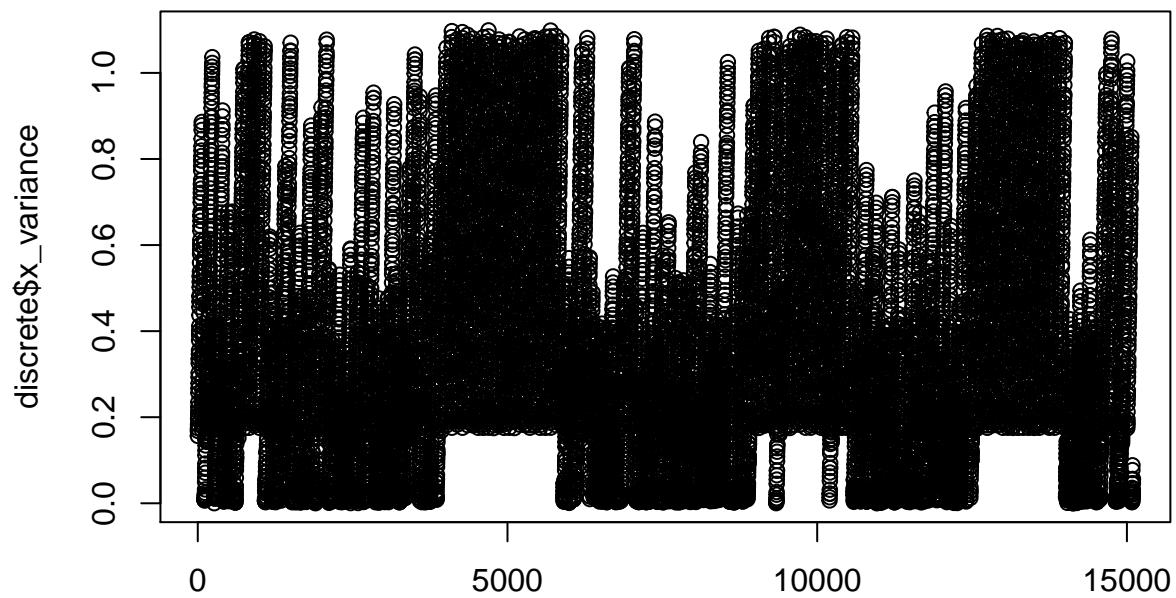
Continuous Filter Y Variance Over Time



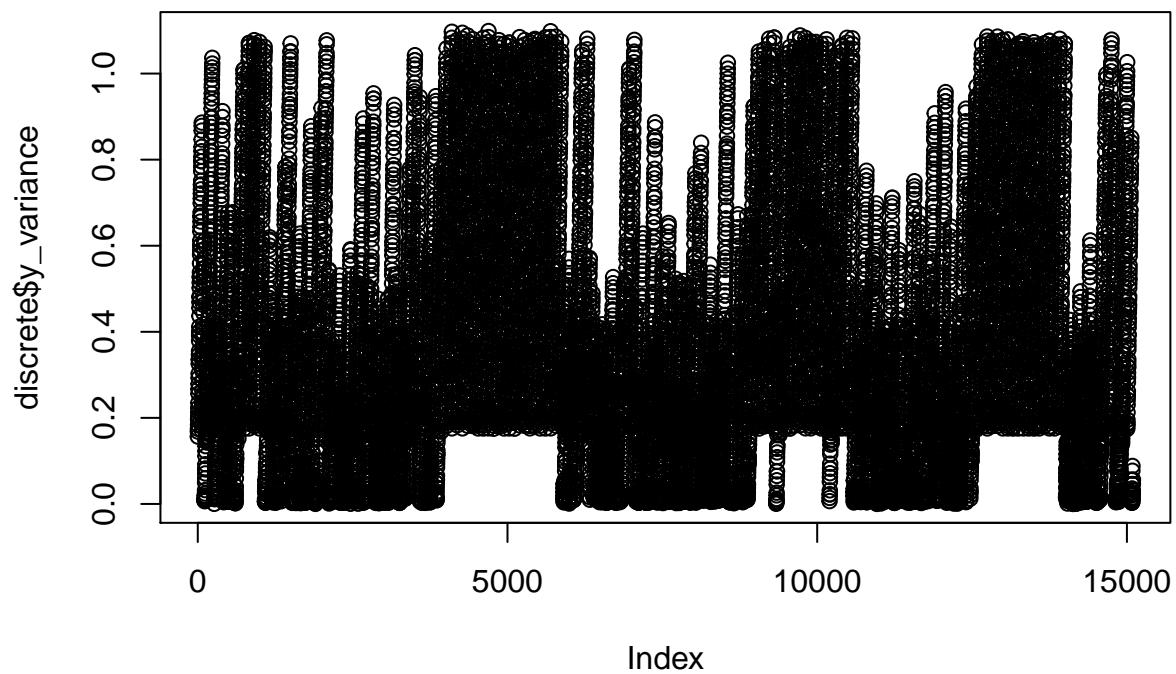
Continuous Filter Yaw Variance Over Time



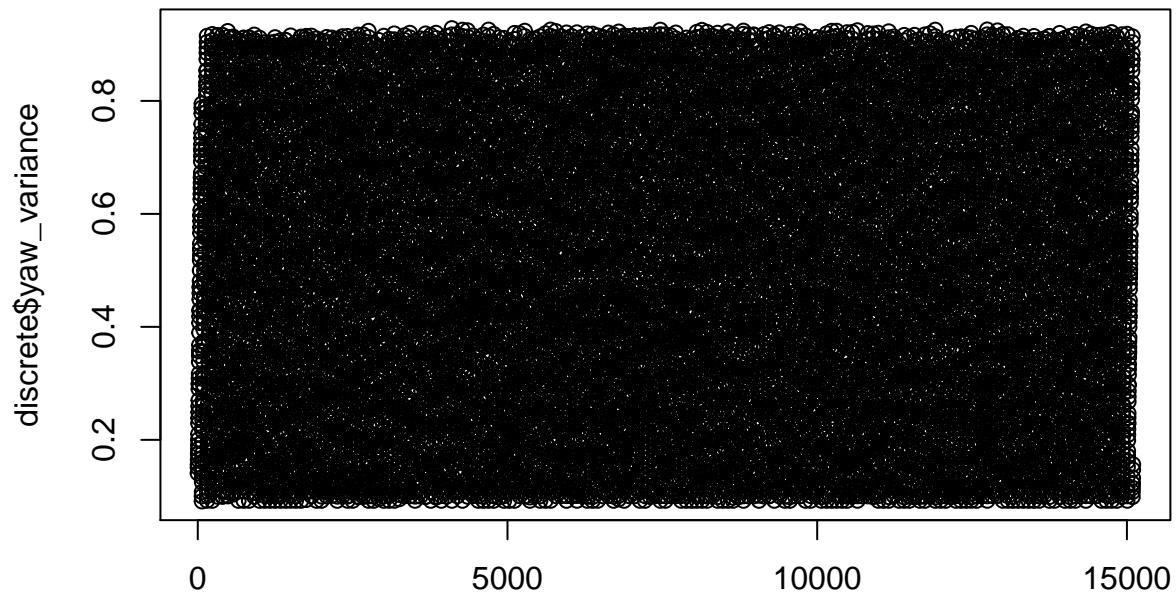
Discrete Filter X Variance Over Time



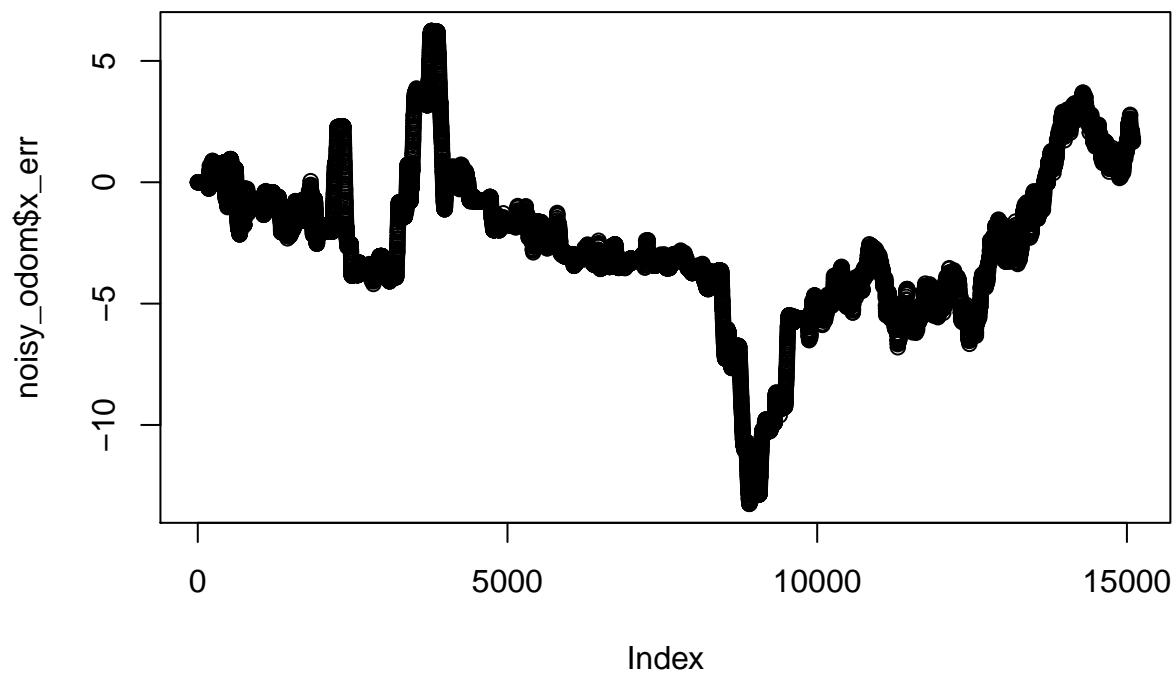
Discrete Filter Y Variance Over Time



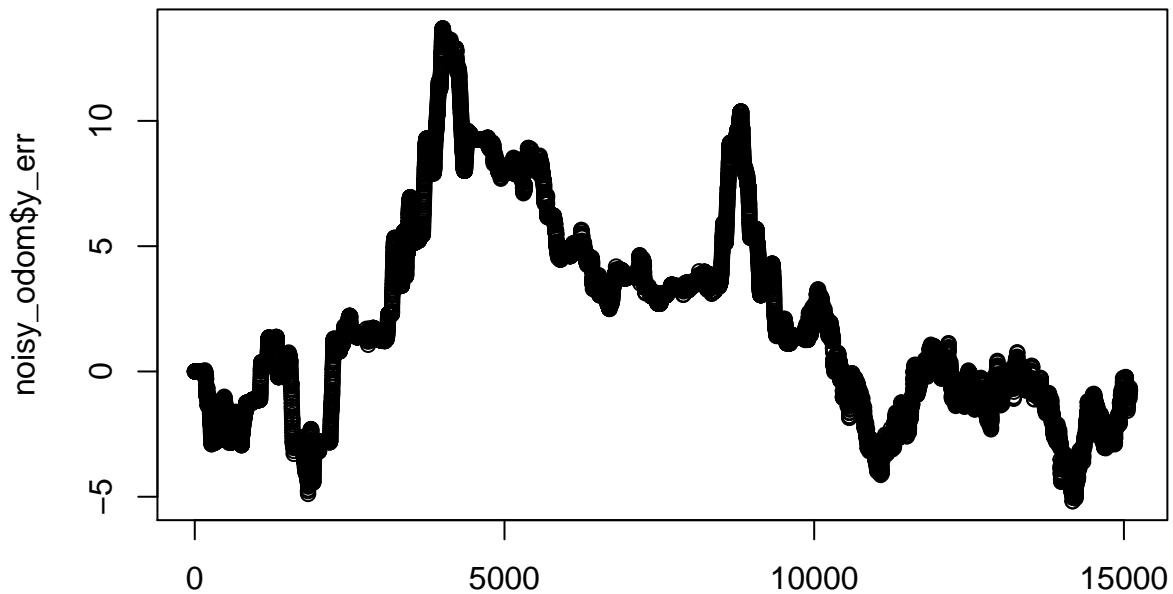
Discrete Filter Yaw Variance Over Time



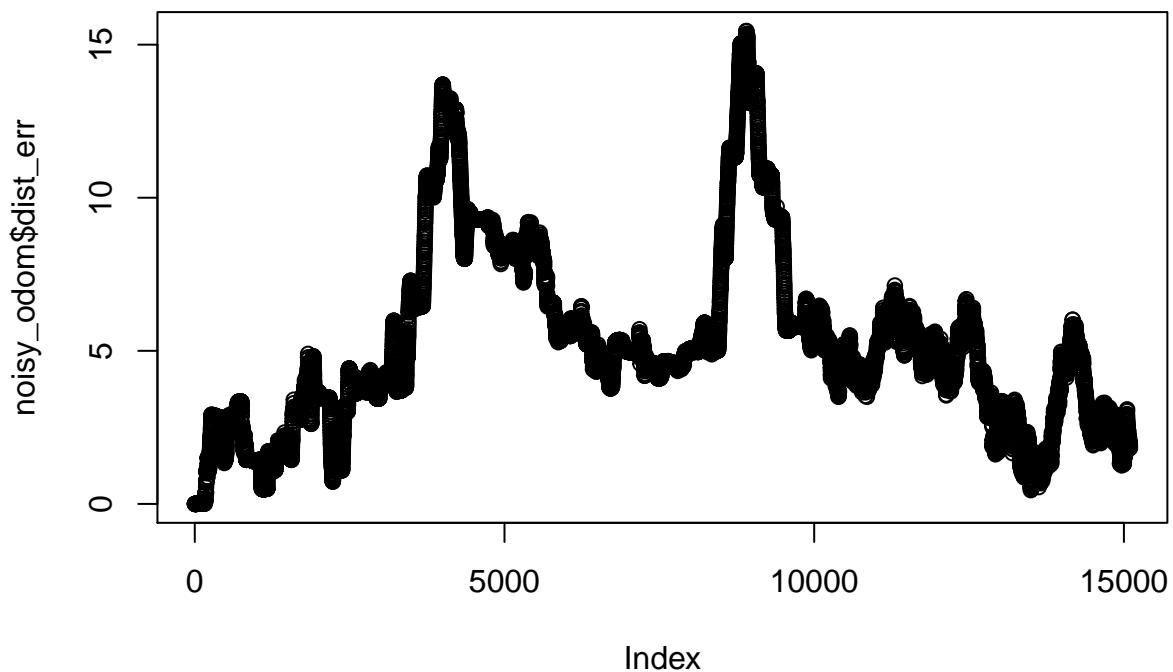
Noisy Odom X Error Over Time



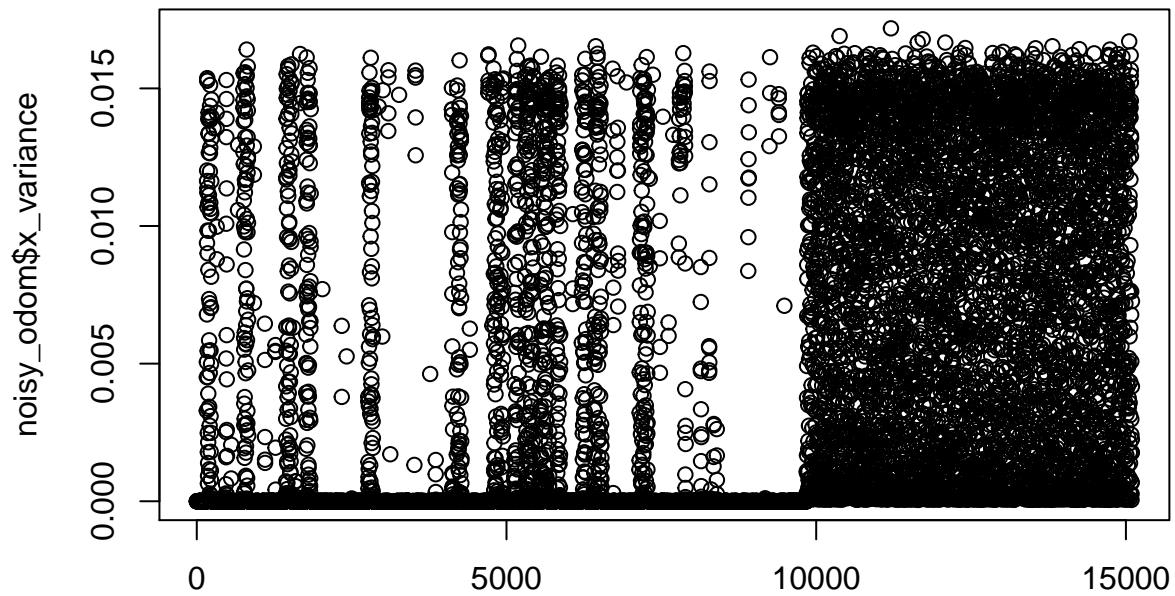
Noisy Odom Y Error Over Time



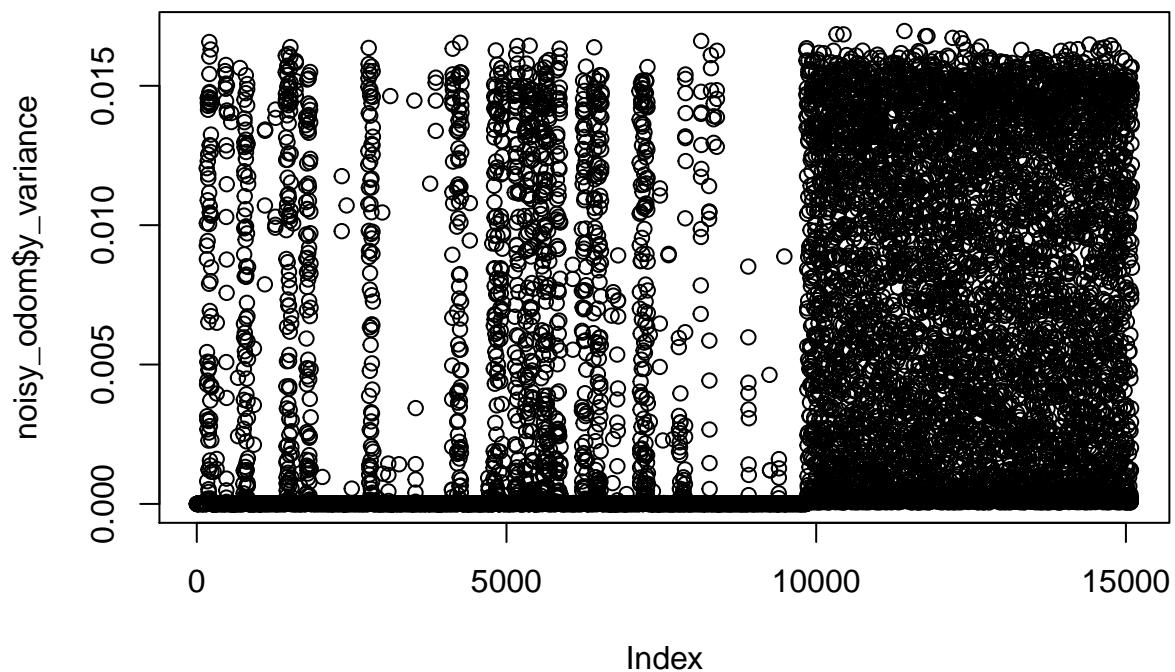
Noisy Odom Horizontal Distance Error Over Time



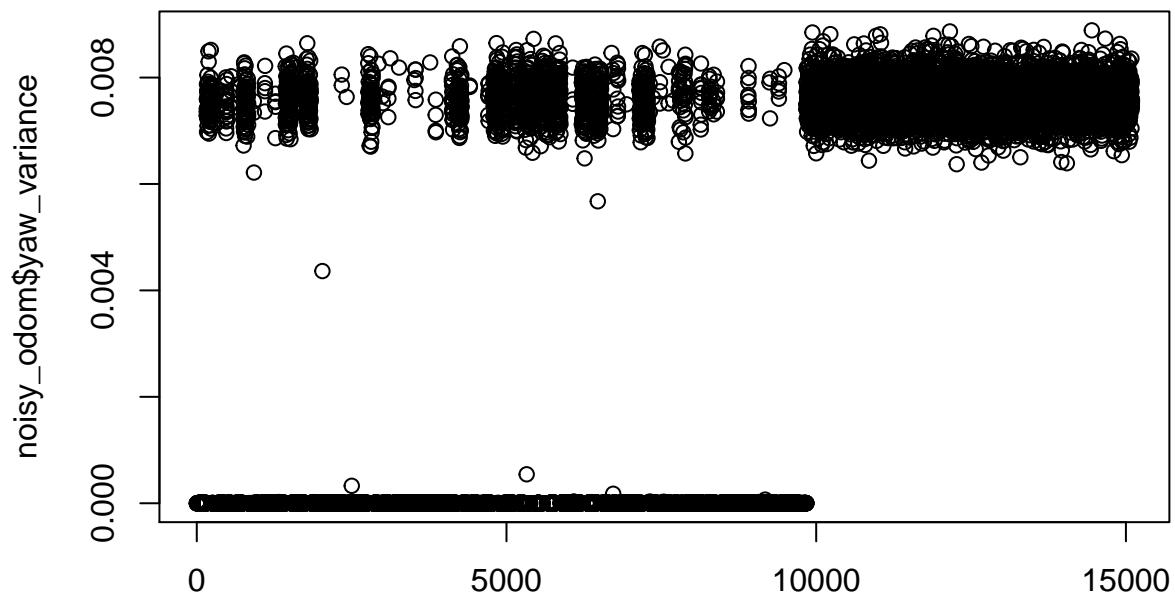
Variance of X Coordinate in Noisy Odometry



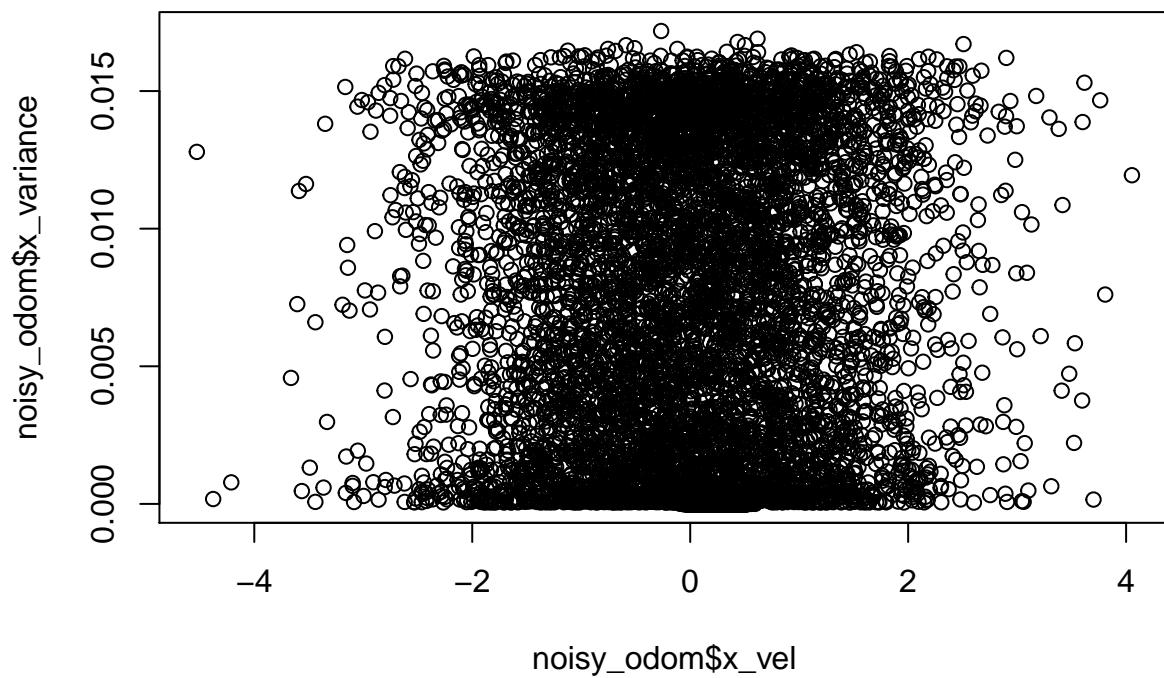
Variance of Y Coordinate in Noisy Odometry



Variance of Yaw Coordinate in Noisy Odometry



Variance vs. Velocity of X in Noisy Odometry



Variance vs. Velocity of Yaw in Noisy Odometry

