

# two\_stationary\_noiseless\_no\_gps Turtlebot 2 Report

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This is a summary of the data from the two\_stationary\_noiseless\_no\_gps experiment, Turtlebot #2.

The runtime of this experiment was 0 hours, 13 minutes, and 47.3 seconds.

The total number of external pose measurements received by the robot during this time was 7823 which means poses were received at an average of 9.4560619 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.
## 0.0000133 0.0020610 0.0041170 0.0041120 0.0061610 0.0082110

summary(continuous$y_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 6.380e-10 1.597e-06 6.245e-06 8.229e-06 1.391e-05 2.428e-05

summary(continuous$yaw_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 3.155e-05 1.606e-03 3.012e-03 2.961e-03 4.448e-03 5.735e-03

summary(continuous$dist_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 0.0000133 0.0020610 0.0041170 0.0041120 0.0061610 0.0082110

summary(discrete$x_error)

##      Min.    1st Qu.     Median      Mean 3rd Qu.      Max.
## 0.03016 0.03228 0.03429 0.03431 0.03639 0.03845

summary(discrete$y_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## -0.009141 -0.007024 -0.005954 -0.005723 -0.003983 -0.002773

summary(discrete$yaw_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 3.155e-05 1.606e-03 3.012e-03 2.961e-03 4.448e-03 5.735e-03

summary(discrete$dist_error)

##      Min.    1st Qu.     Median      Mean 3rd Qu.      Max.
## 0.03029 0.03248 0.03481 0.03481 0.03701 0.03952

summary(noisy_odom$x_err)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 6.174e-06 1.280e-05 1.494e-05 1.461e-05 1.690e-05 2.186e-05
```

```

summary(noisy_odom$y_err)

##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## -3.234e-07 -2.013e-07 -1.365e-07 -1.415e-07 -6.110e-08 -3.113e-09

summary(noisy_odom$dist_err)

##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 6.174e-06 1.280e-05 1.494e-05 1.461e-05 1.690e-05 2.186e-05

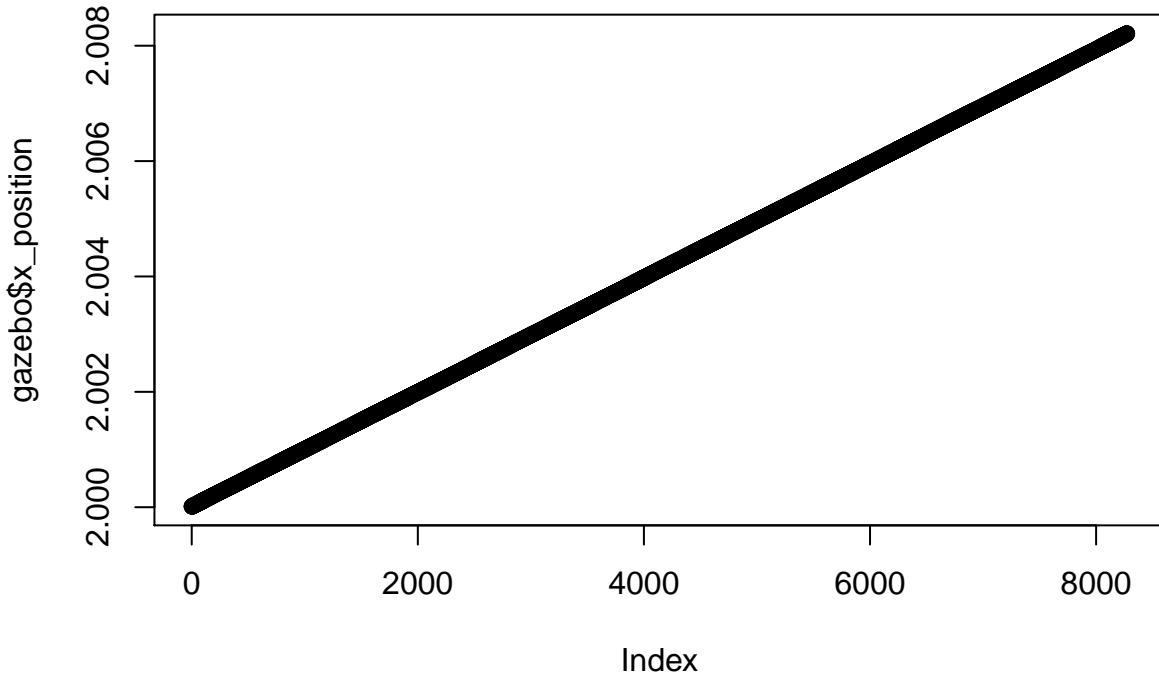
if (NROW(gps) > 0) {
  summary(gps$x_err)
  summary(gps$y_err)
  summary(gps$dist_err)
}

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

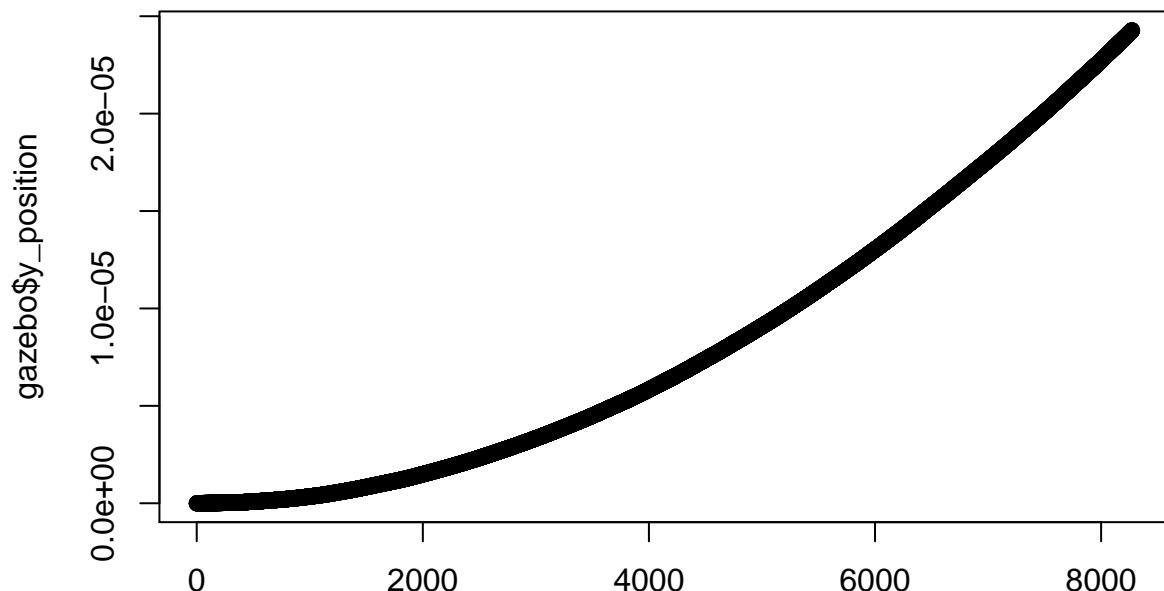
##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 7.582e-16 8.794e-15 1.819e-14 2.395e-14 3.228e-14 2.047e-13

```

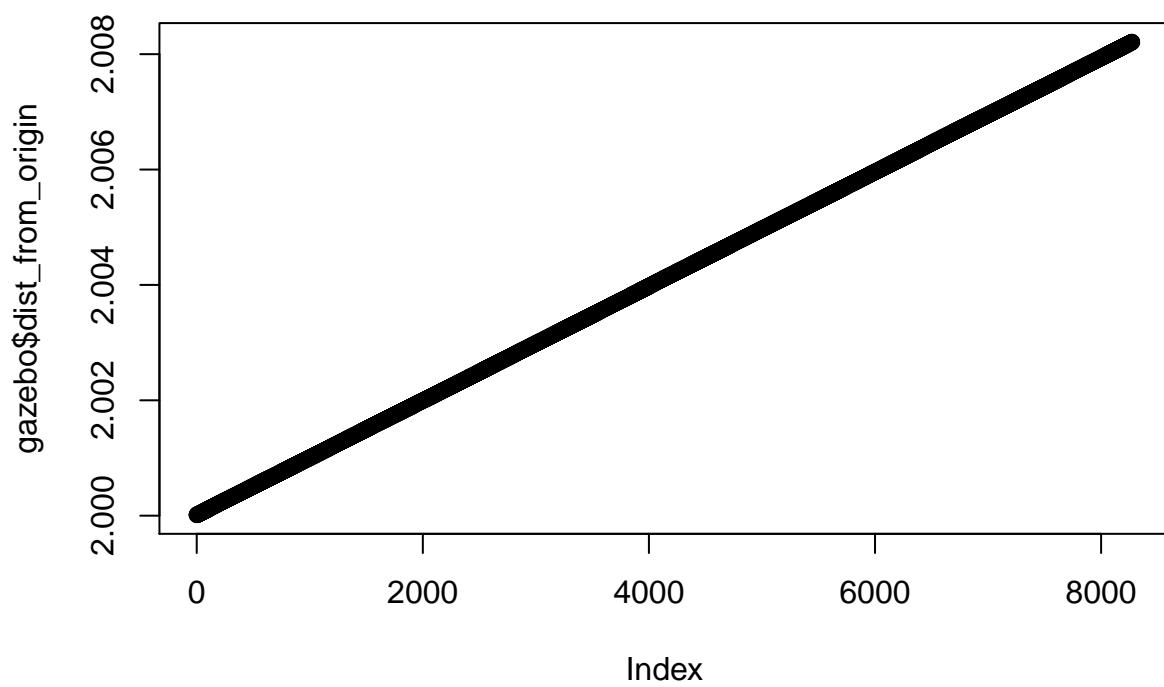
### X coordinate of robot over time



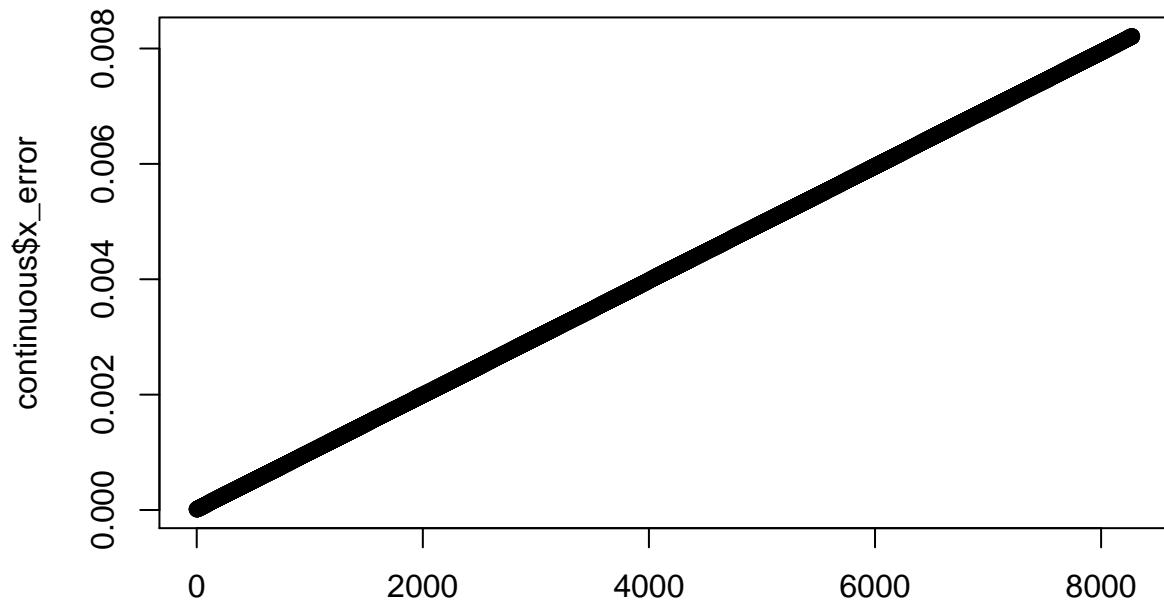
**Y coordinate of robot over time**



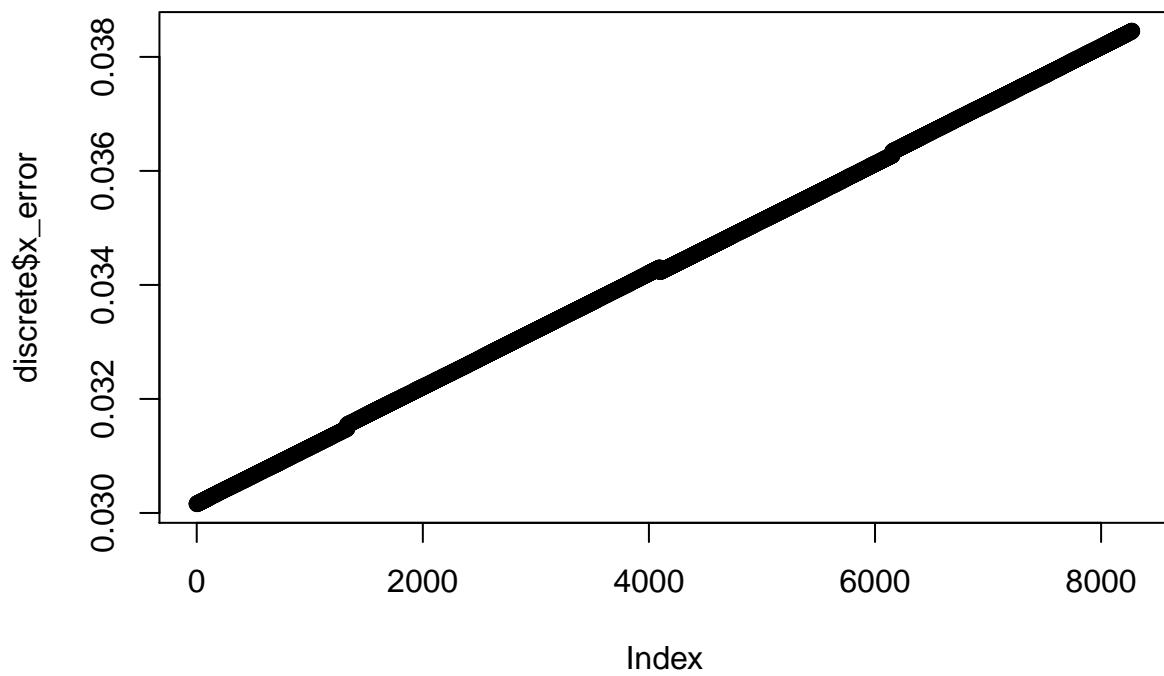
**Distance from origin vs. time<sup>Index</sup>**



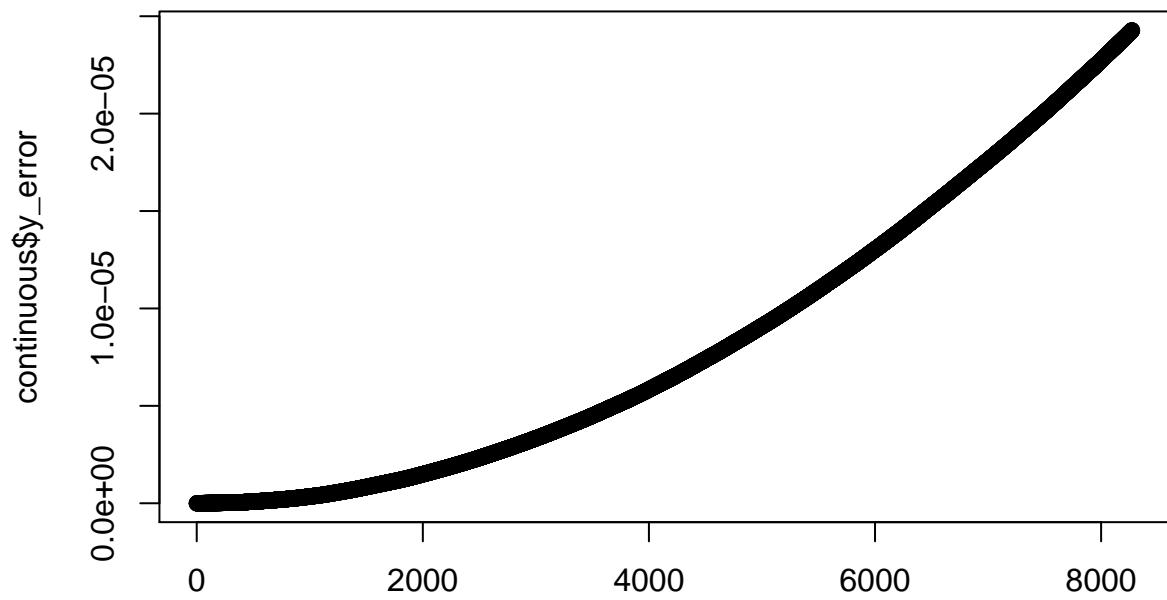
**Continuous x\_error over time**



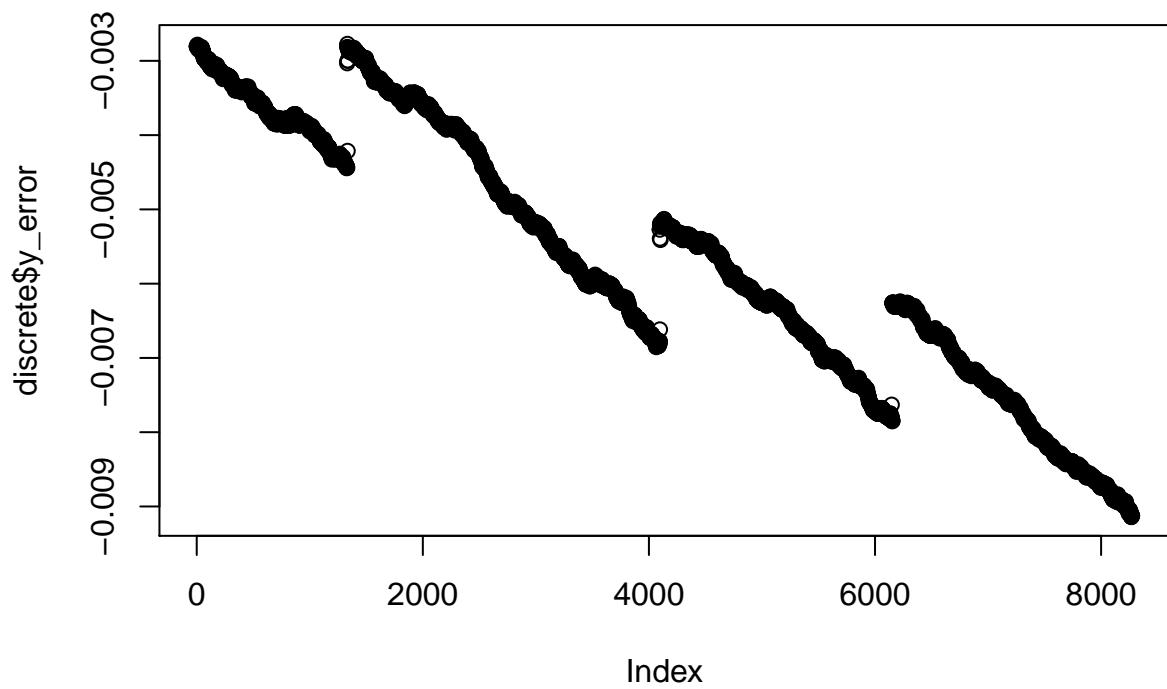
**Discrete x\_error over time**



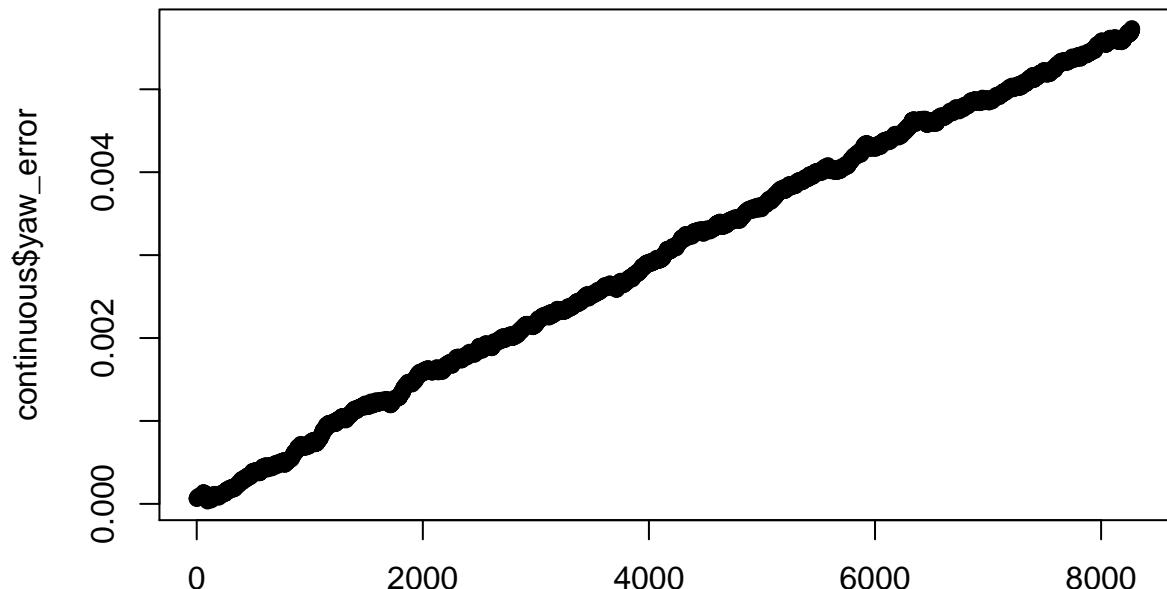
**Continuous y\_error over time**



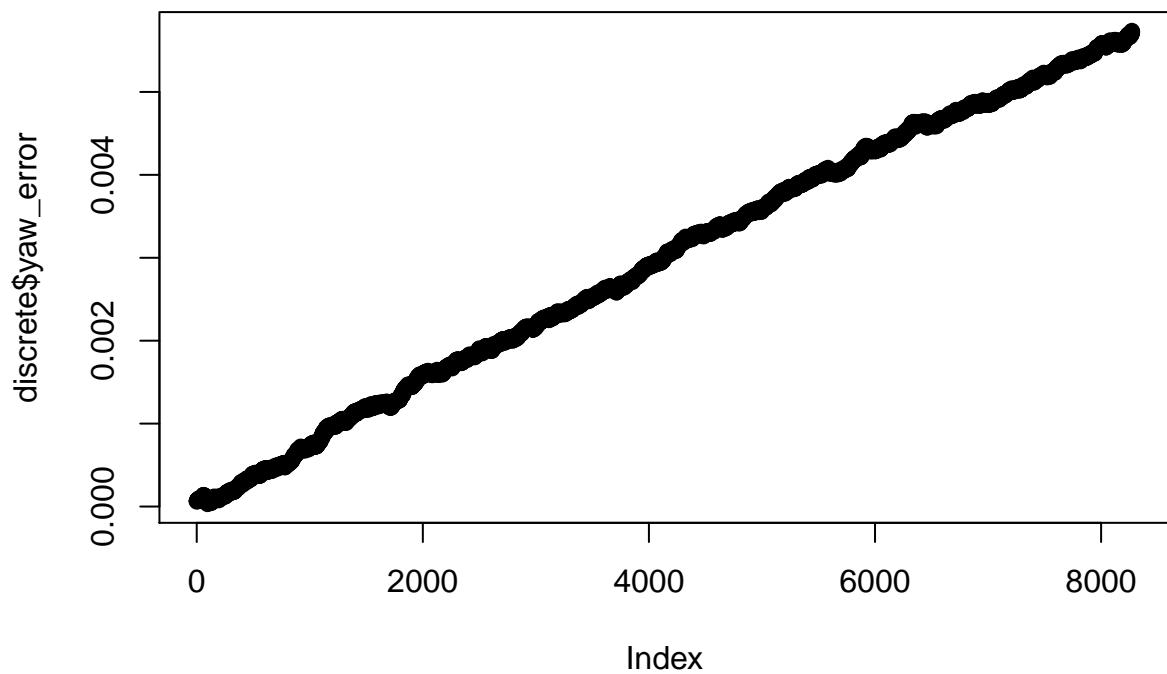
**Discrete y\_error over time**



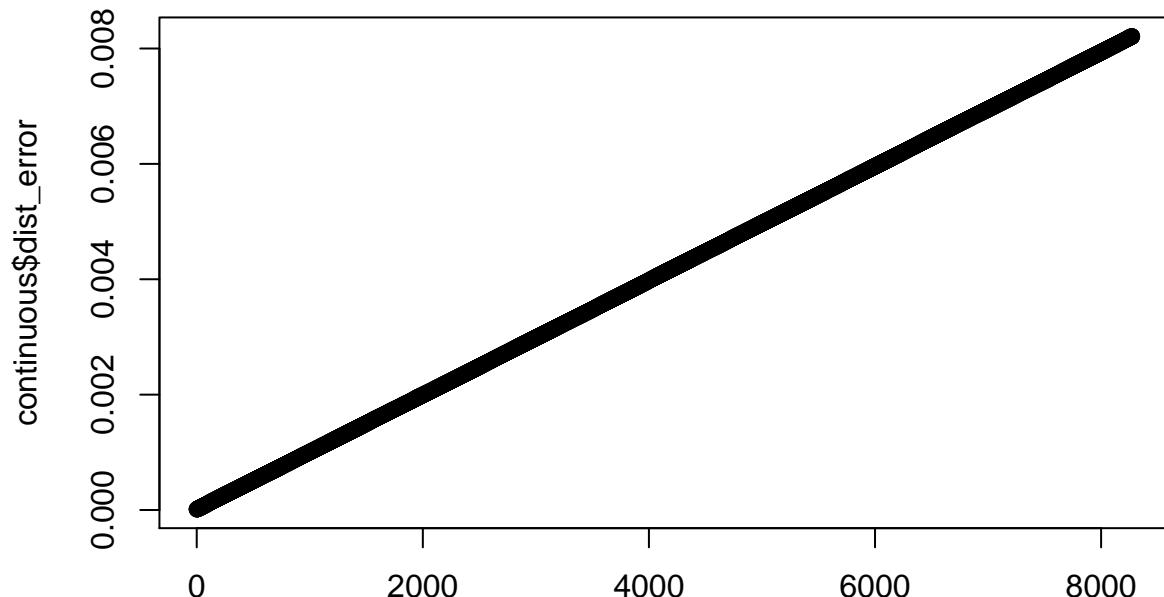
**Continuous yaw error over time**



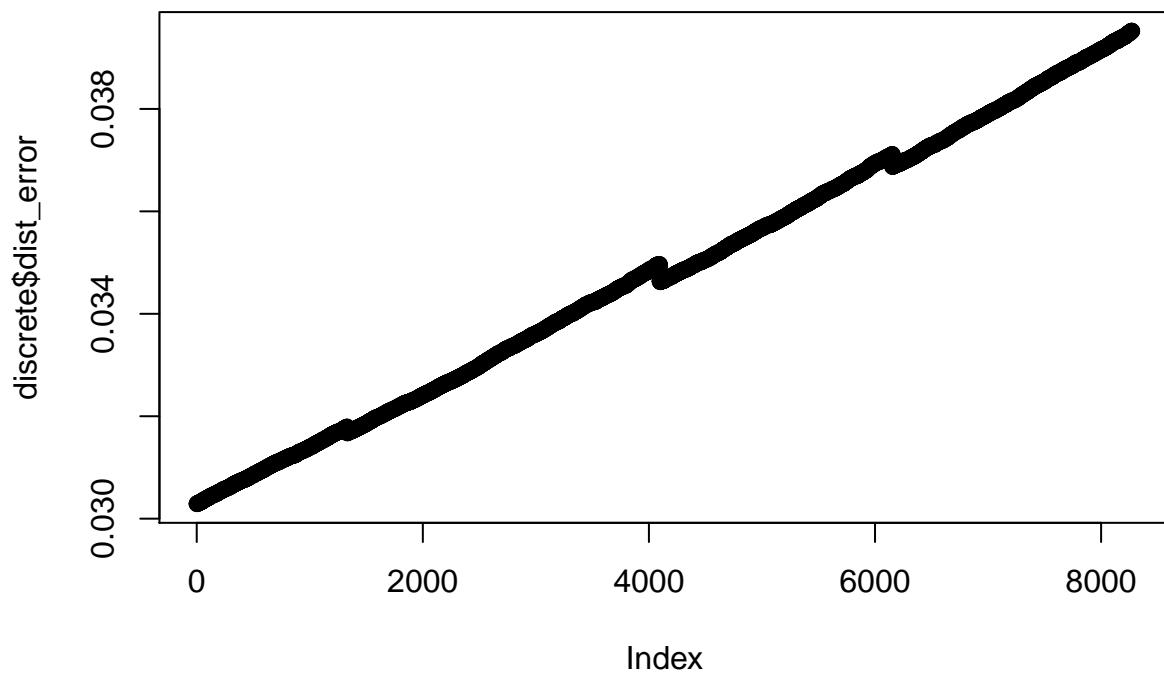
**Discrete yaw error over time**



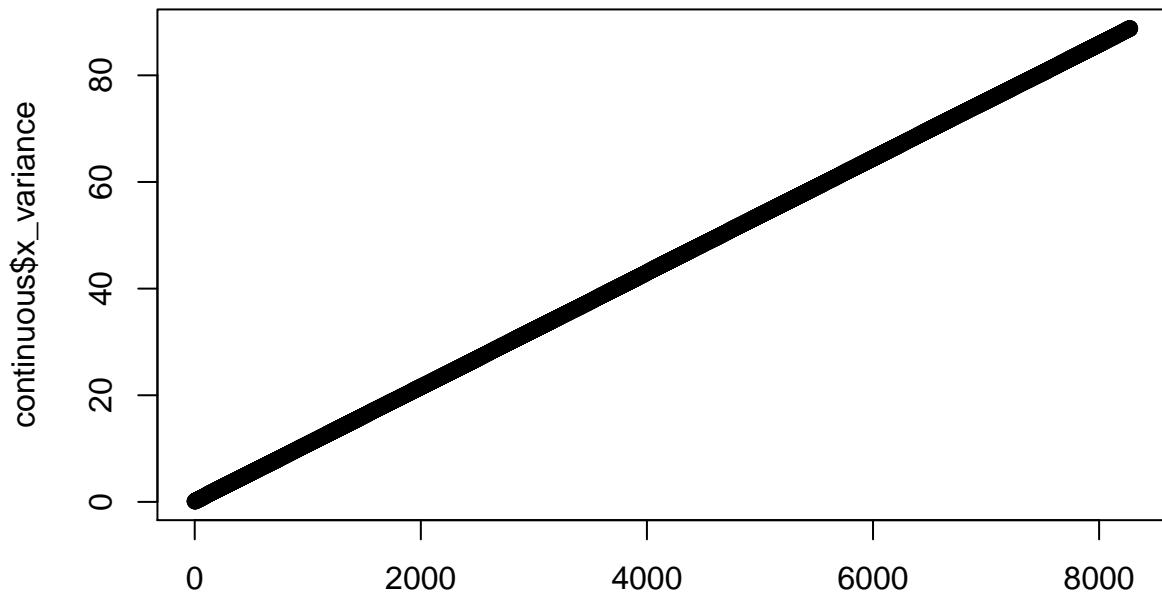
**Continuous total distance error over time**



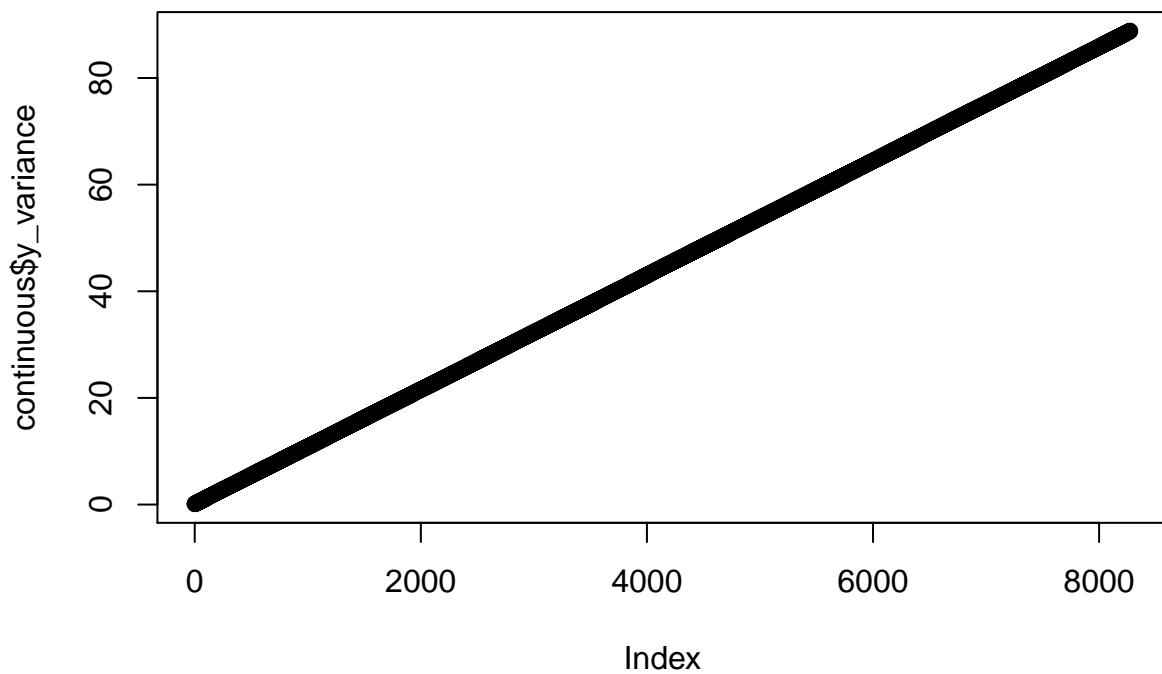
**Discrete total distance error over time**



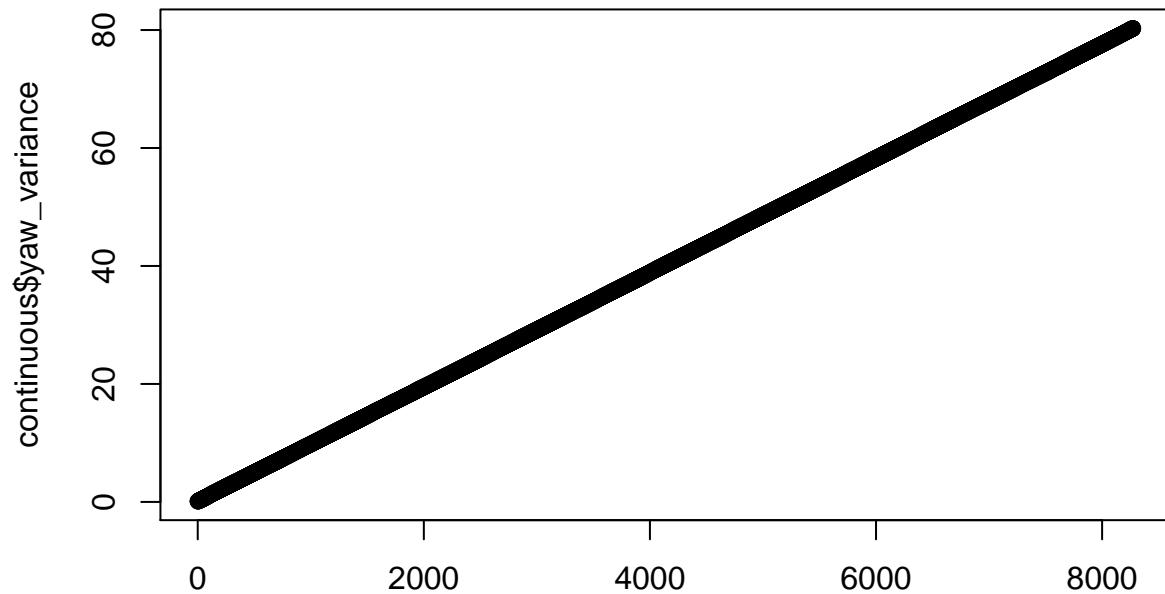
**Continuous Filter X Variance Over Time**



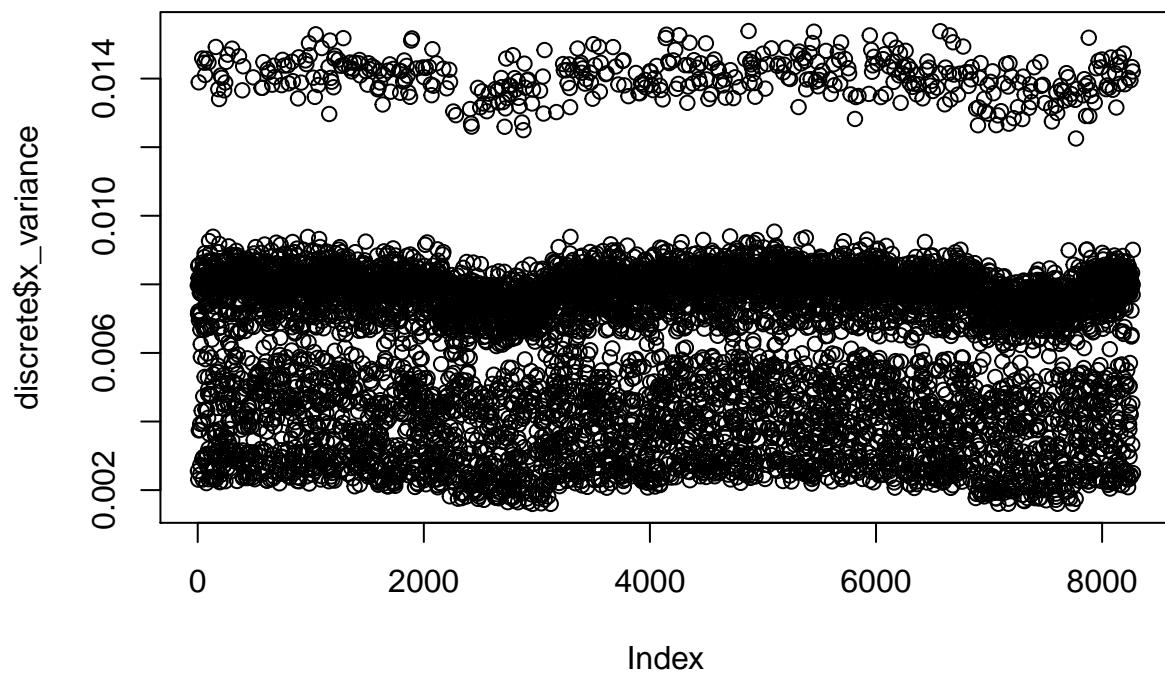
**Continuous Filter Y Variance Over Time**



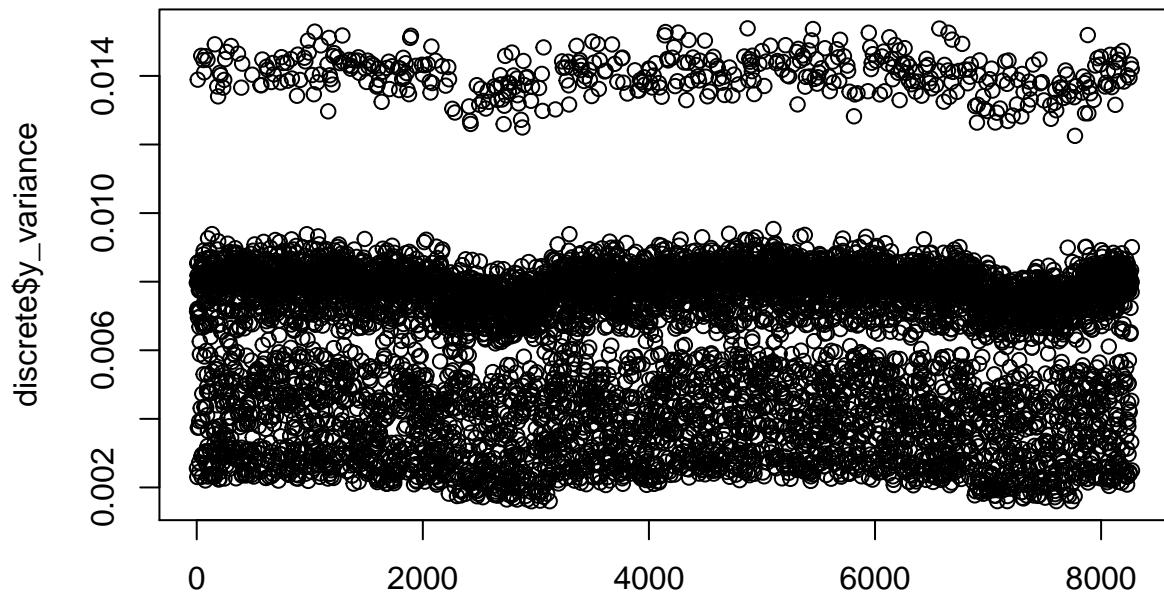
**Continuous Filter Yaw Variance Over Time**



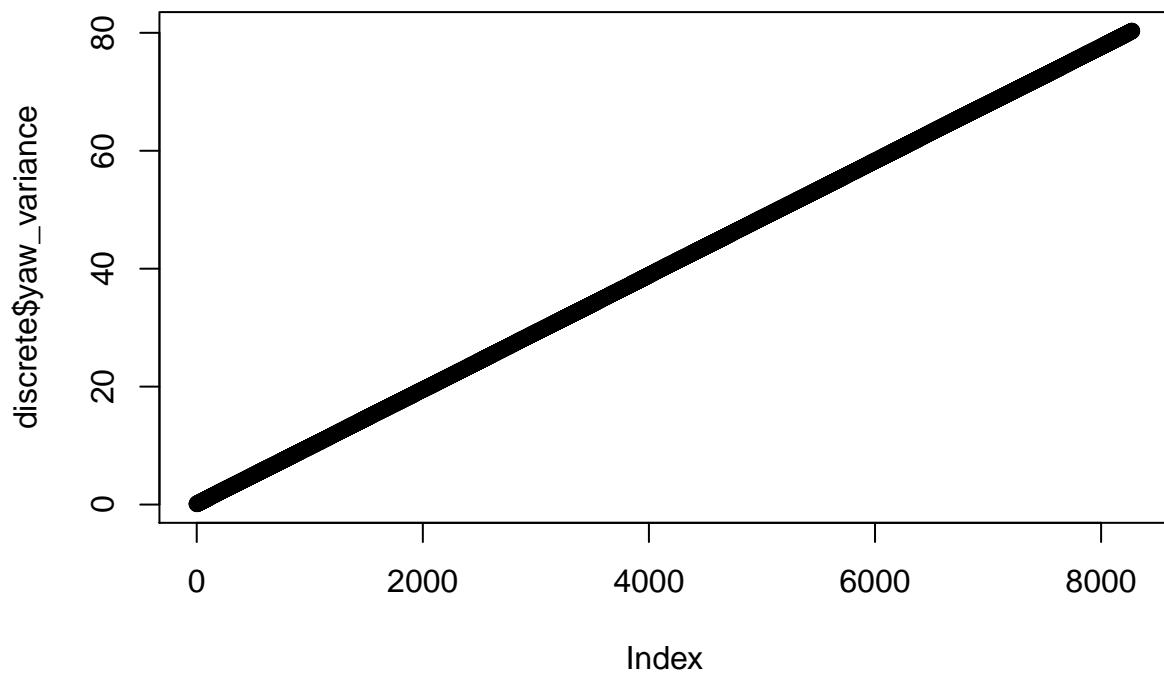
**Discrete Filter X Variance Over Time**



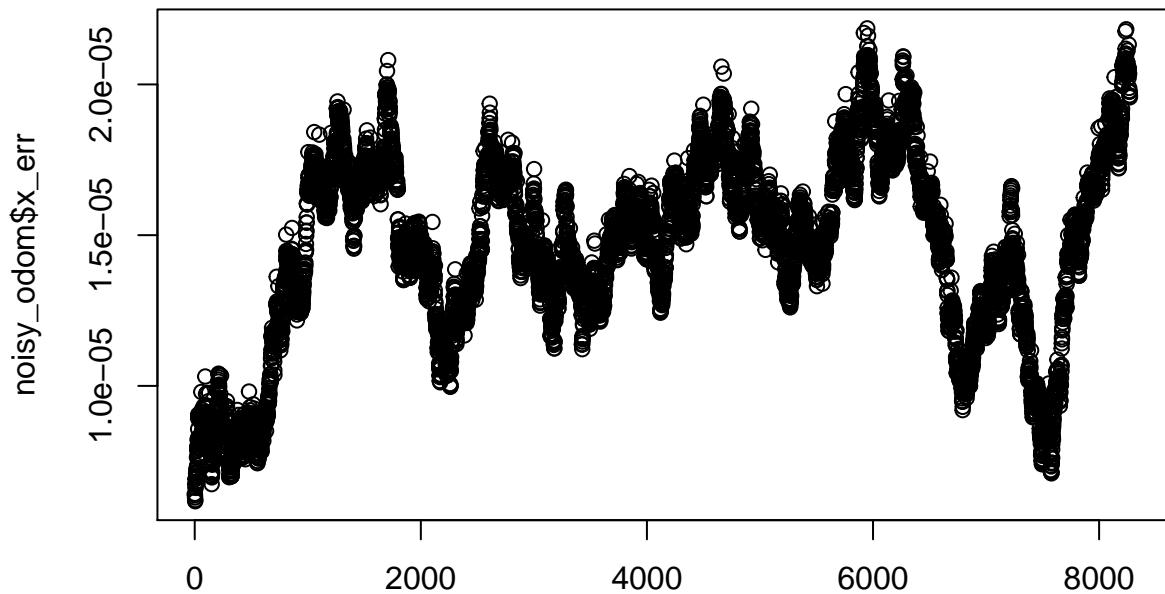
**Discrete Filter Y Variance Over Time**



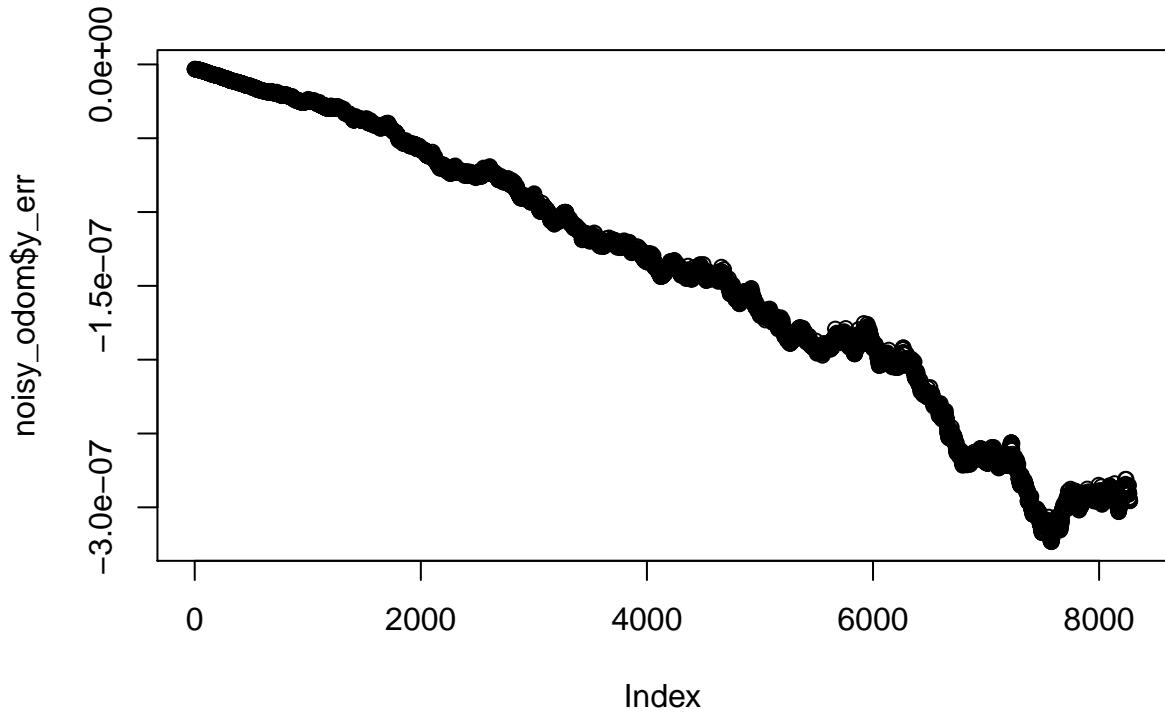
**Discrete Filter Yaw Variance Over Time**



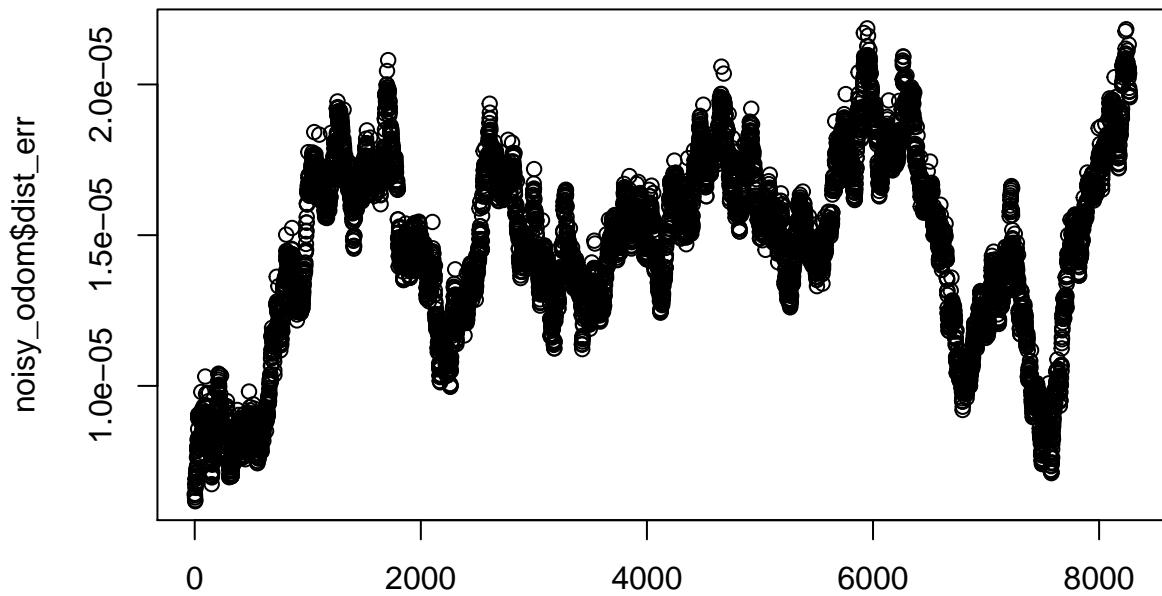
**Noisy Odom X Error Over Time**



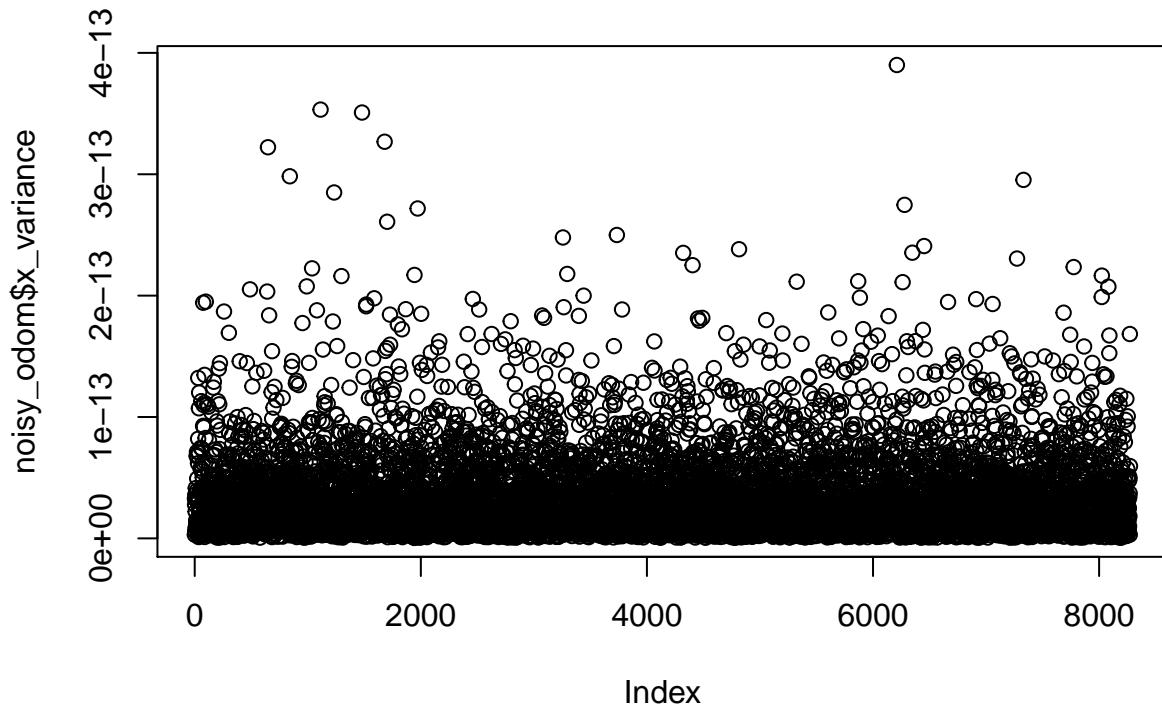
**Noisy Odom Y Error Over Time**



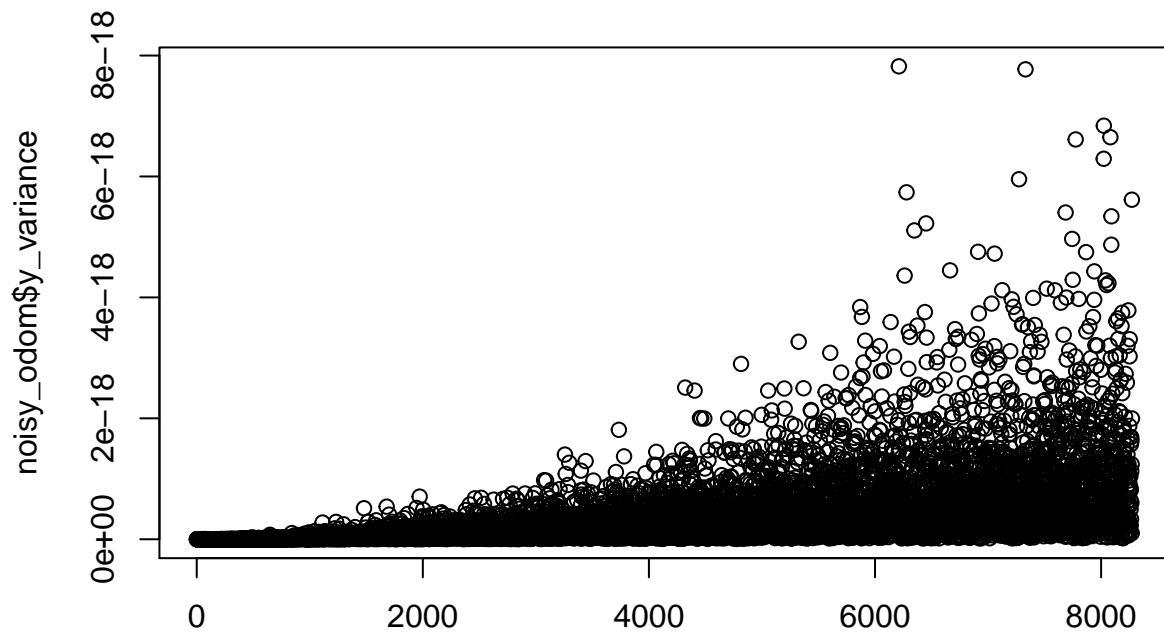
### Noisy Odom Horizontal Distance Error Over Time



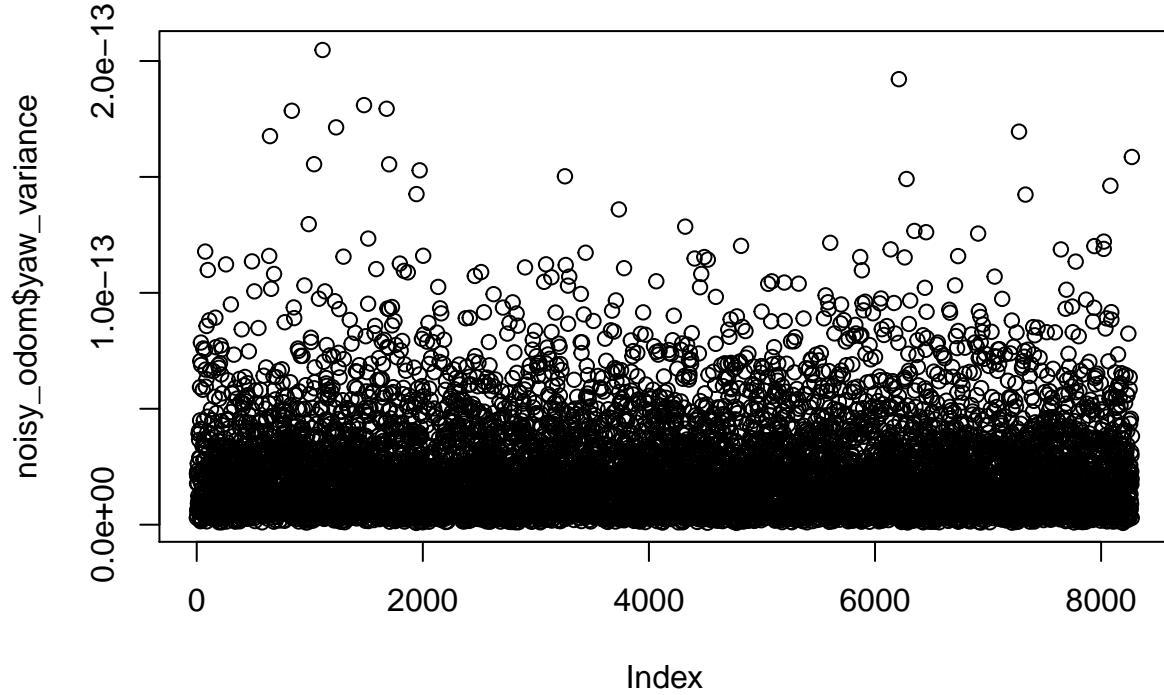
Variance of X Coordinate in Noisy Odometry



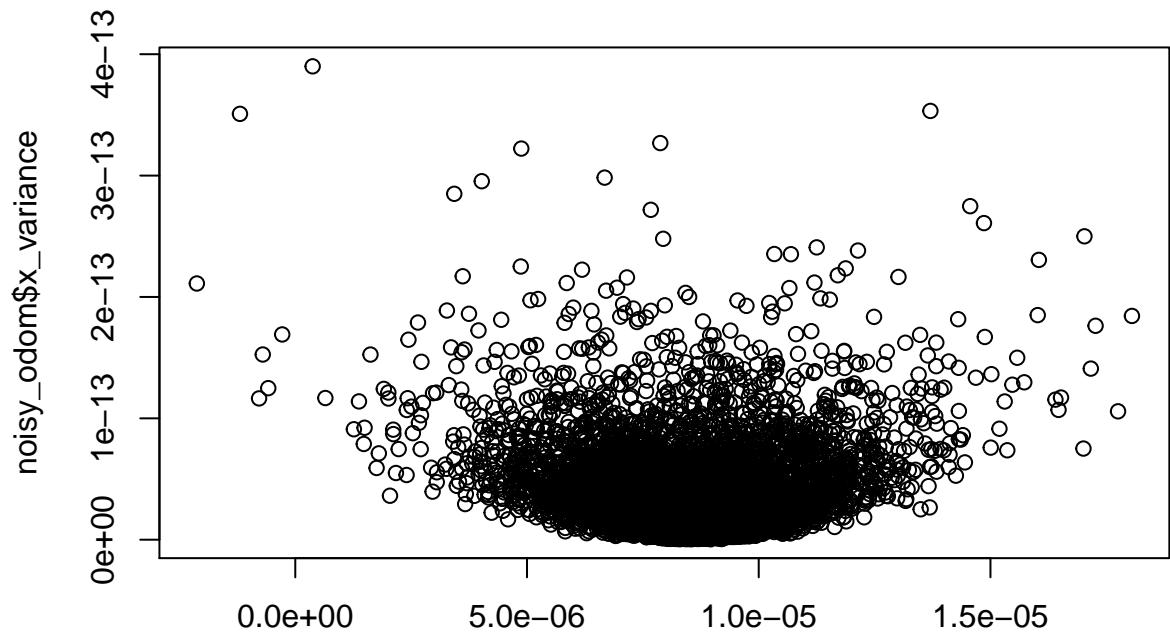
**Variance of Y Coordinate in Noisy Odometry**



**Variance of Yaw Coordinate in Noisy Odometry**



**Variance vs. Velocity of X in Noisy Odometry**



**Variance vs. Velocity of Yaw in Noisy Odometry**

