

two_mobile_no_gps Turtlebot 1 Report

Matthew Swartwout

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

The runtime of this experiment was 0 hours, 6 minutes, and 49.5 seconds.

The total number of external pose measurements received by the robot during this time was 879 which means poses were received at an average of 2.1465201 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.  
## -171.6000 -118.5000 -68.3300 -71.4900 -18.5500 0.9379
```

```
summary(continuous$y_error)
```

```
##      Min. 1st Qu. Median     Mean 3rd Qu.      Max.  
## -3.119   5.409  25.130  26.380  45.020  66.040
```

```
summary(continuous$yaw_error)
```

```
##      Min. 1st Qu. Median     Mean 3rd Qu.      Max.  
## -3.1410 -1.4540  0.1476  0.1469  1.7570  3.1410
```

```
summary(continuous$dist_error)
```

```
##      Min. 1st Qu. Median     Mean 3rd Qu.      Max.  
## 0.00002 19.32000 72.81000 76.62000 126.80000 183.90000
```

```
summary(discrete$x_error)
```

```
##      Min. 1st Qu. Median     Mean 3rd Qu.      Max.  
## -301.400 -294.200 -261.100 -217.200 -170.400  8.054
```

```
summary(discrete$y_error)
```

```
##      Min. 1st Qu. Median     Mean 3rd Qu.      Max.  
## -59.3500 -52.0300 -45.2400 -41.8800 -37.8500  0.1331
```

```
summary(discrete$yaw_error)
```

```
##      Min. 1st Qu. Median     Mean 3rd Qu.      Max.  
## -3.1410 -1.4480  0.1534  0.1486  1.7600  3.1380
```

```
summary(discrete$dist_error)
```

```
##      Min. 1st Qu. Median     Mean 3rd Qu.      Max.  
## 0.00002 174.70000 266.50000 222.20000 298.50000 304.70000
```

```
summary(noisy_odom$x_err)
```

```
##      Min. 1st Qu. Median     Mean 3rd Qu.      Max.  
## -5.3370 -3.2520 -1.1220 -1.3800  0.2969  2.1890
```

```

summary(noisy_odom$y_err)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## -7.90500 -3.26100 -0.66770 -1.54100 -0.02656 1.36600

summary(noisy_odom$dist_err)

##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## 0.000062 0.969400 1.893000 2.774000 4.499000 8.888000

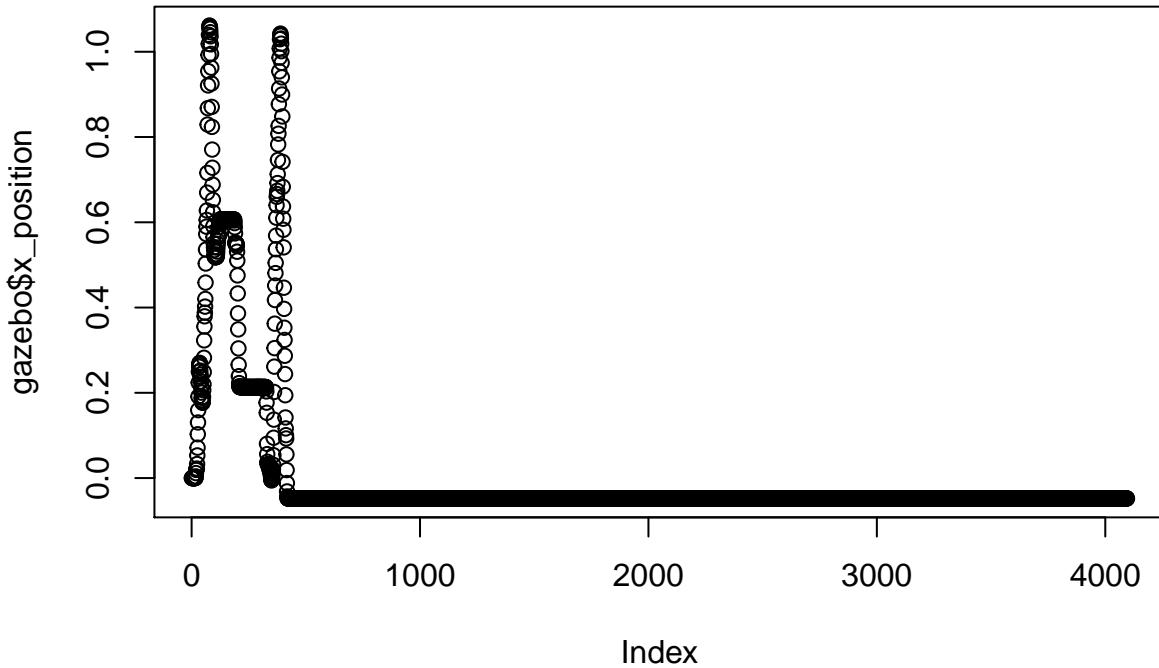
if (NROW(gps) > 0) {
  summary(gps$x_err)
  summary(gps$y_err)
  summary(gps$dist_err)
}

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

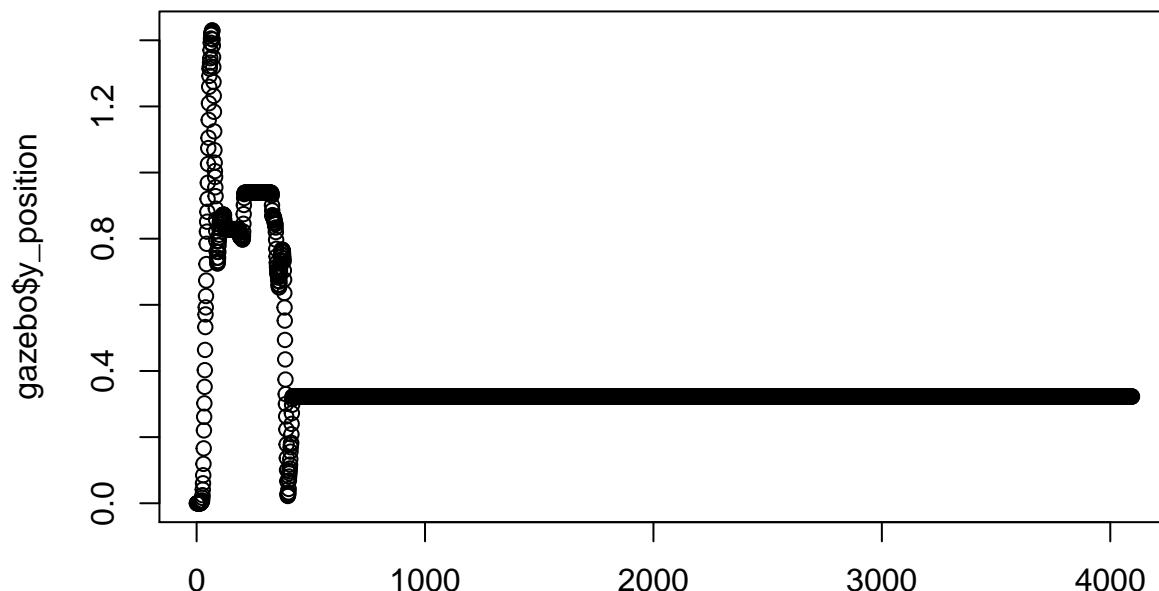
##      Min. 1st Qu. Median     Mean 3rd Qu.    Max.
## 0.000000 0.007213 0.007532 0.006474 0.007790 0.008894

```

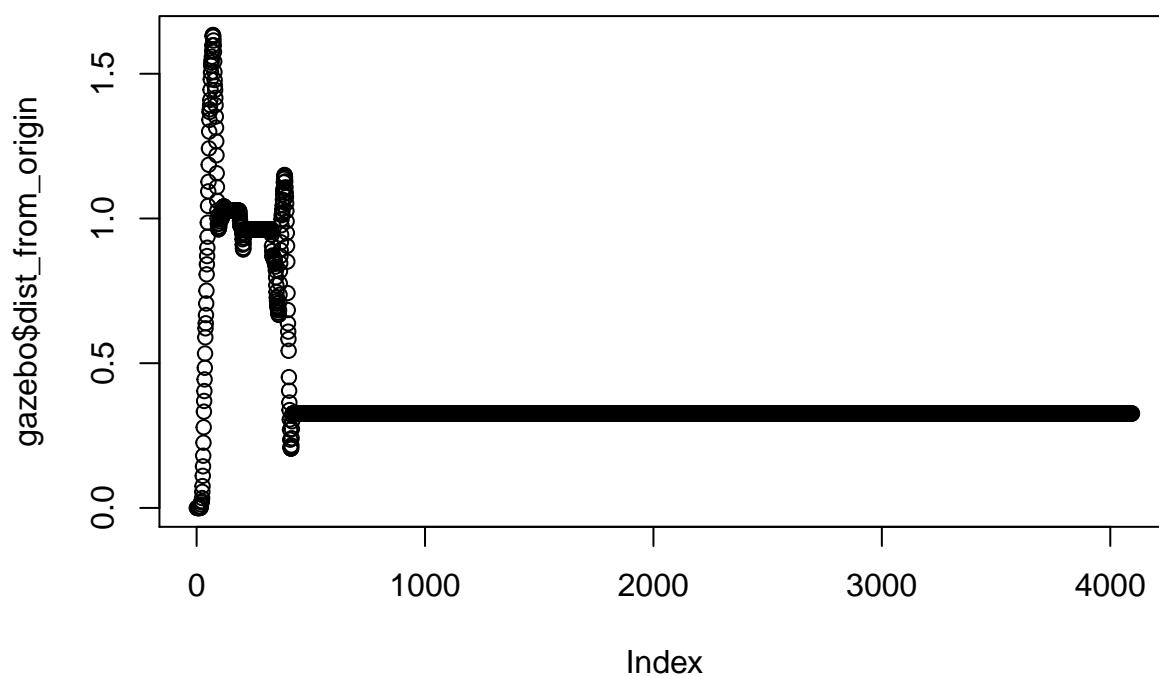
X coordinate of robot over time



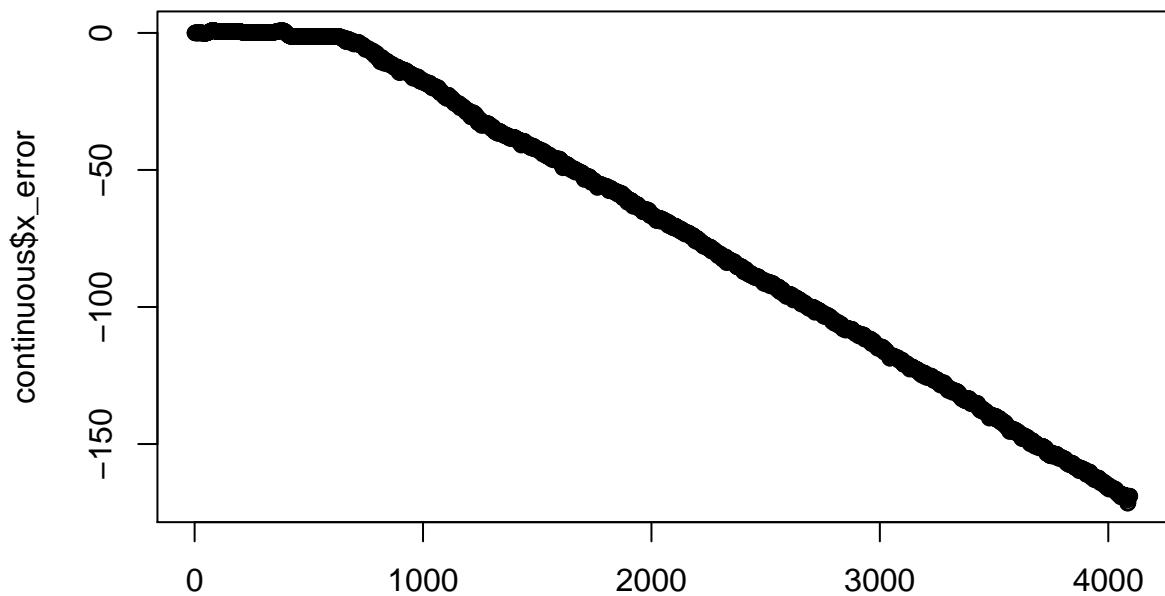
Y coordinate of robot over time



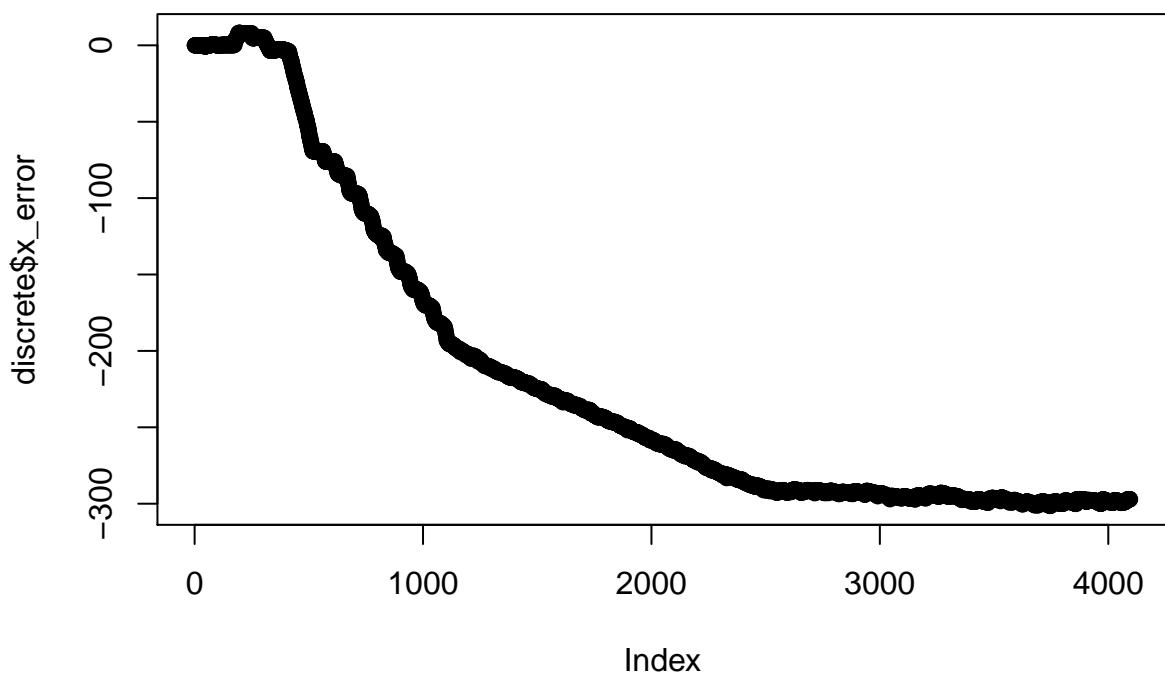
Distance from origin vs. time



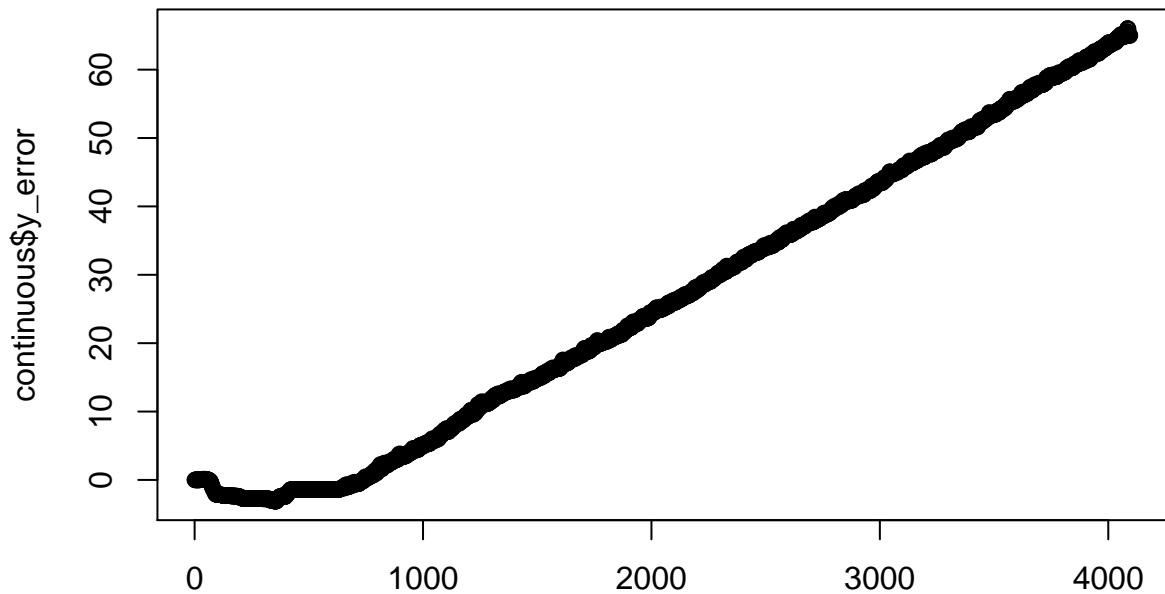
Continuous x_error over time



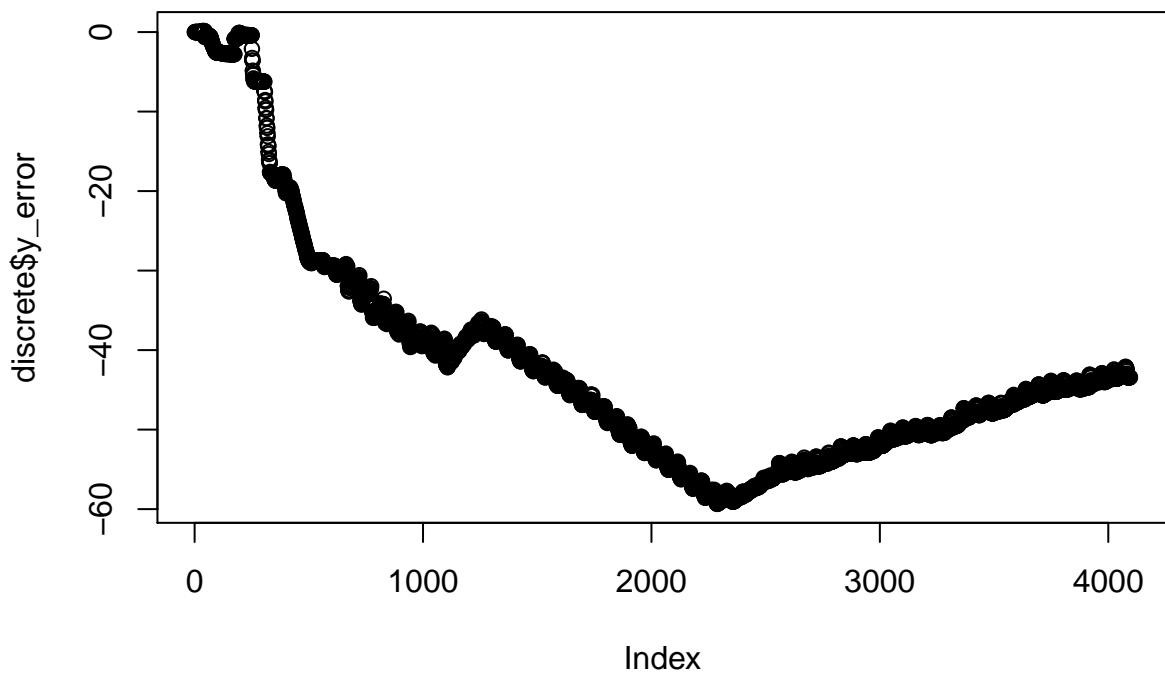
Discrete x_error over time



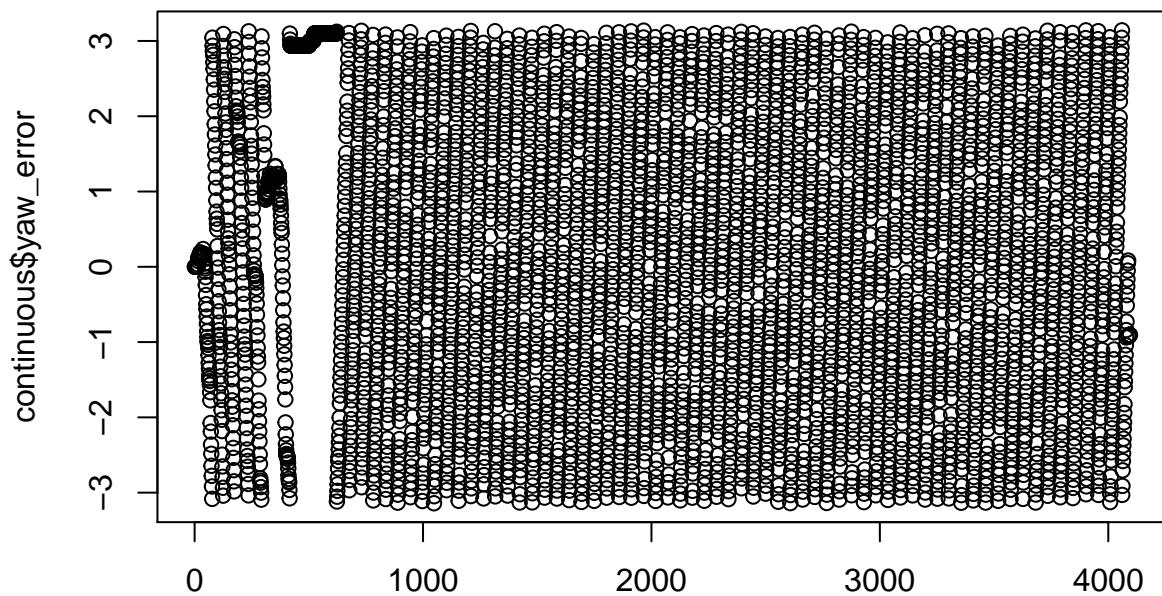
Continuous y_error over time



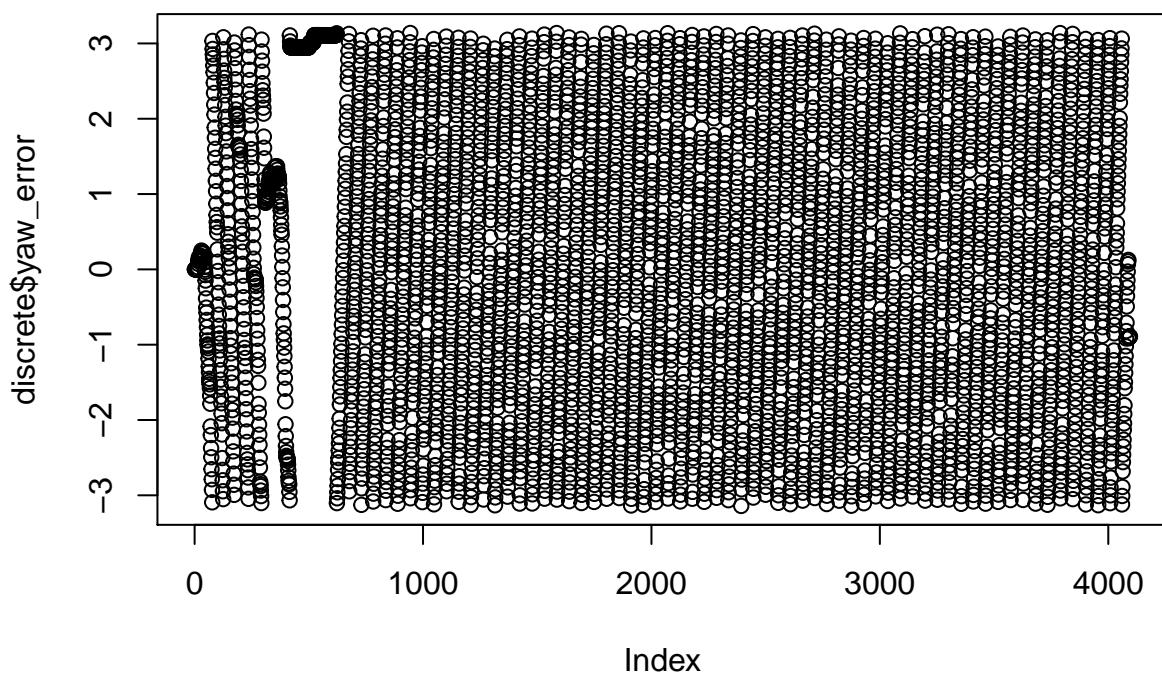
Discrete y_error over time



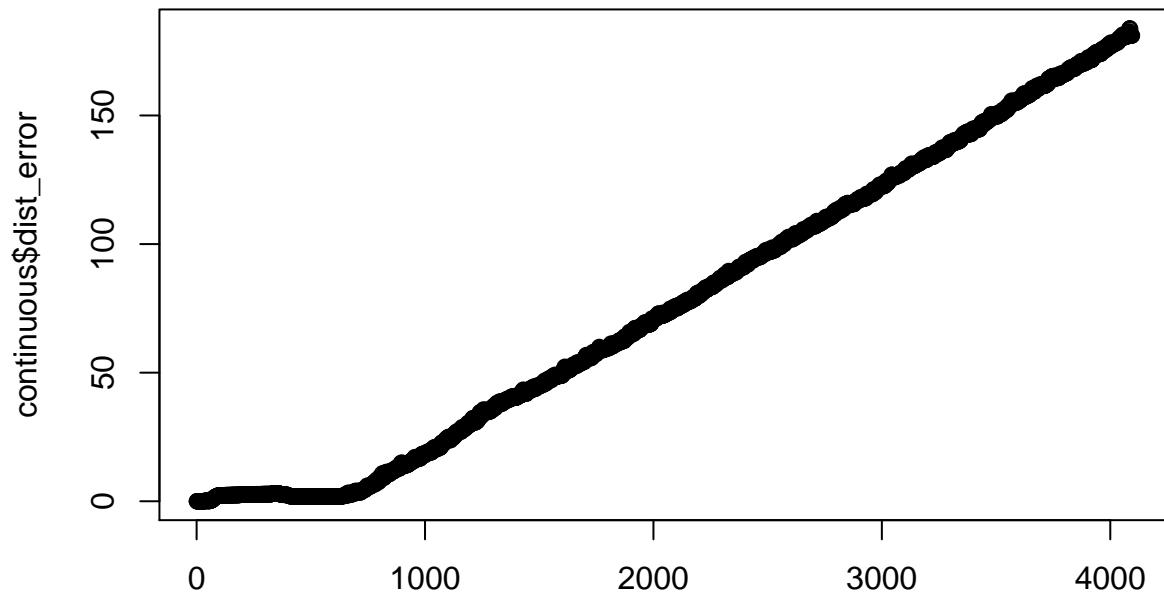
Continuous yaw error over time



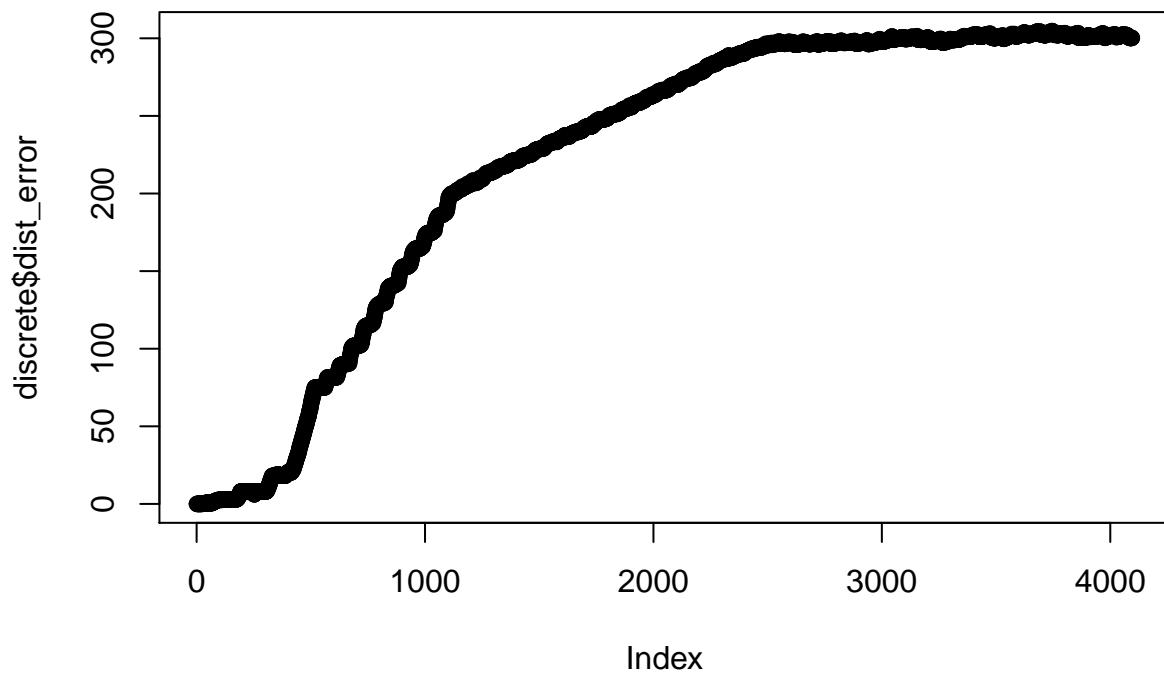
Discrete yaw error over time



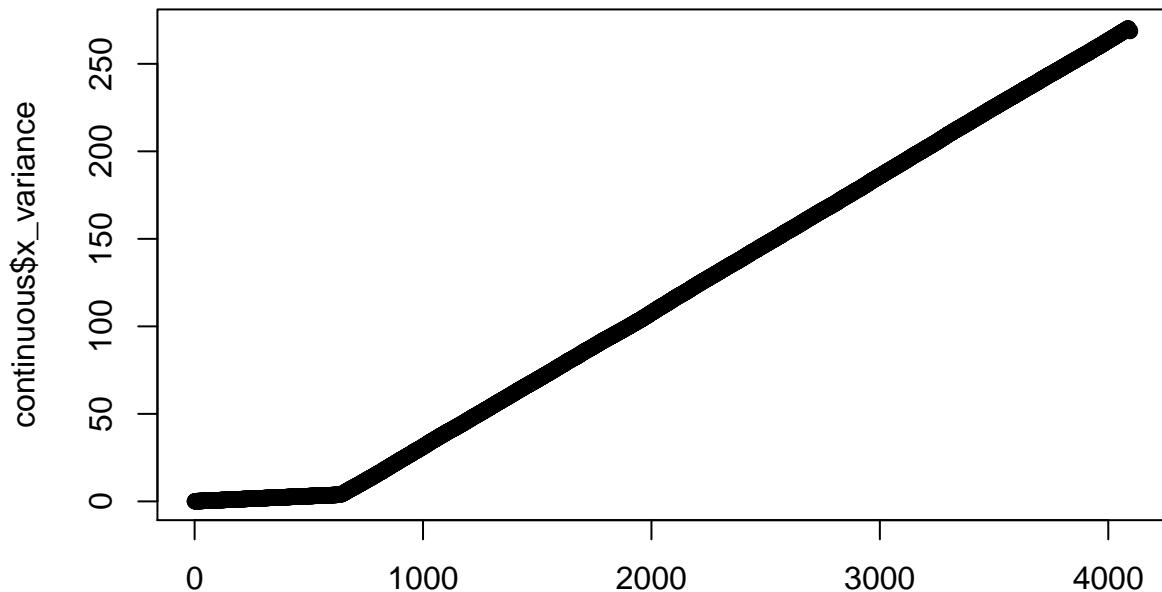
Continuous total distance error over time



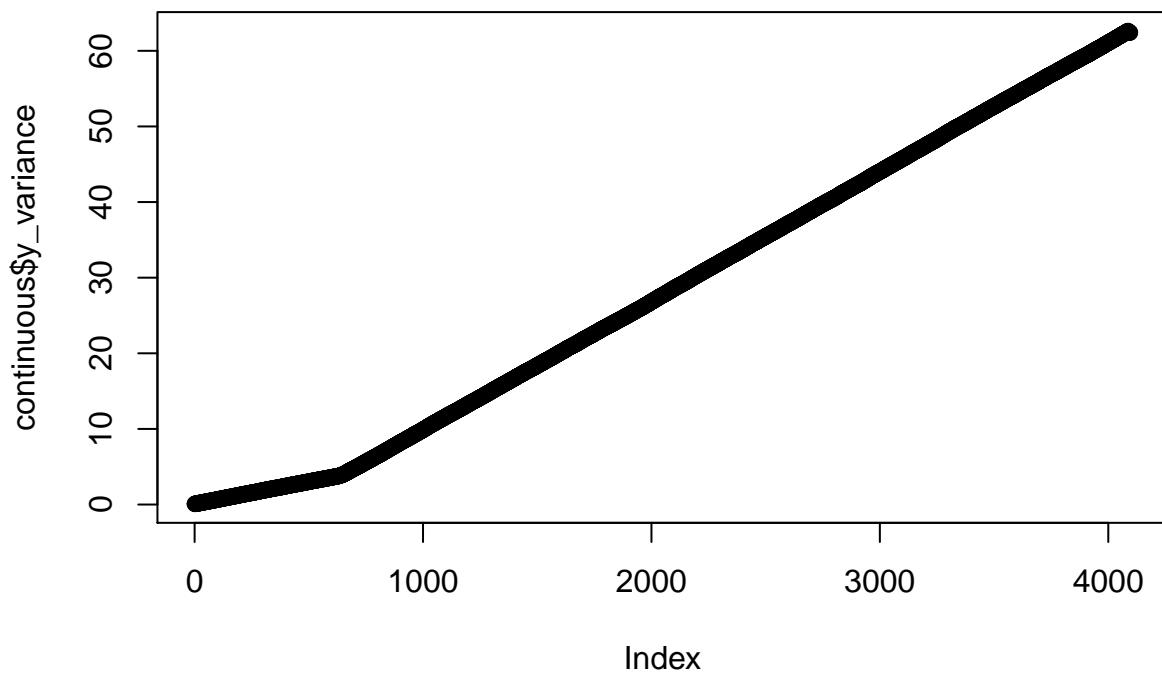
Discrete total distance error over time



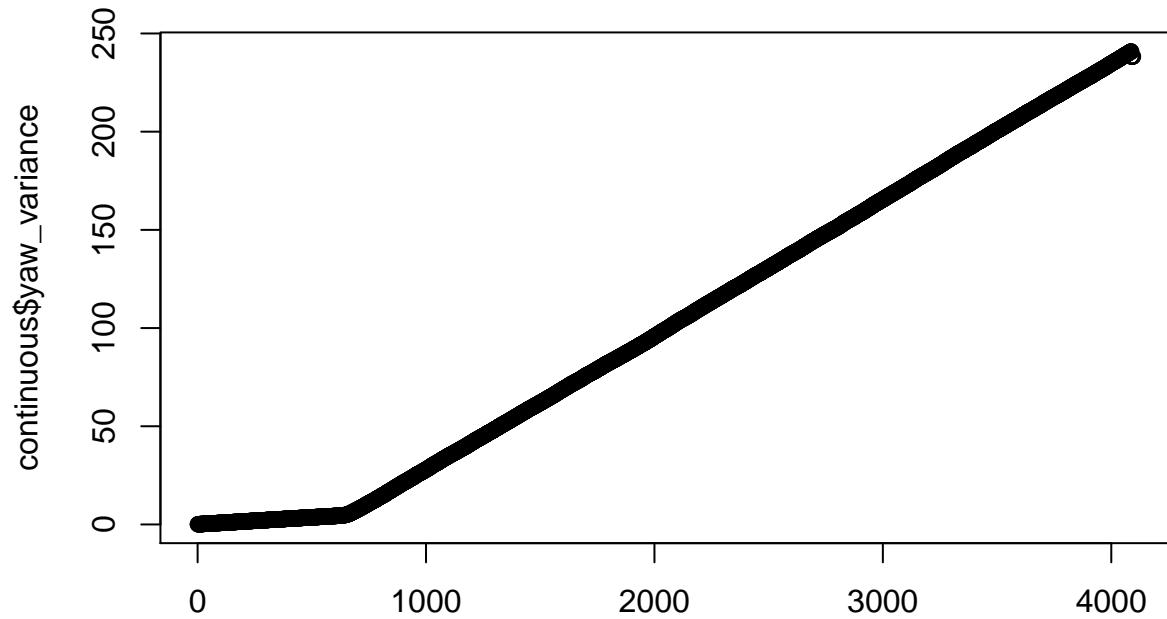
Continuous Filter X Variance Over Time



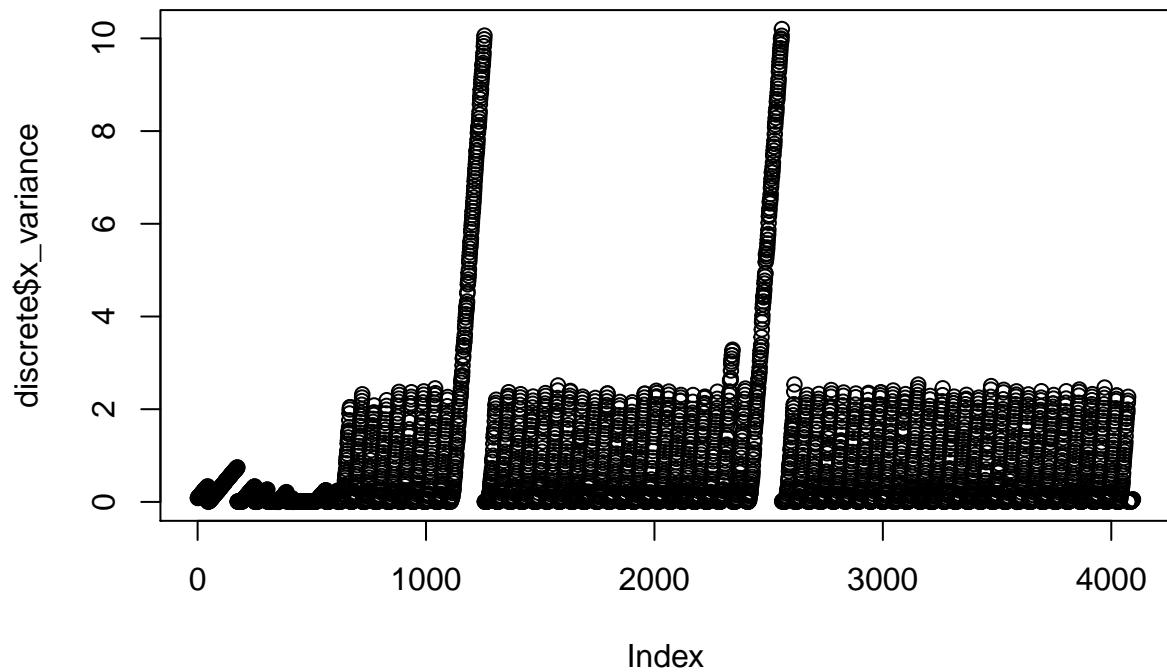
Continuous Filter Y Variance Over Time



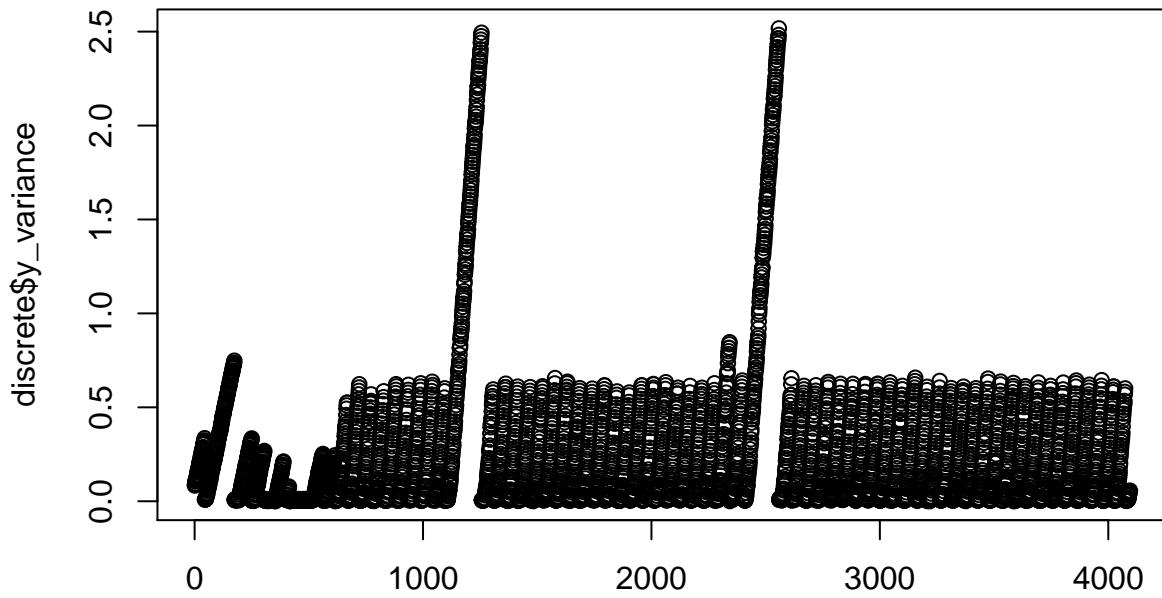
Continuous Filter Yaw Variance Over Time



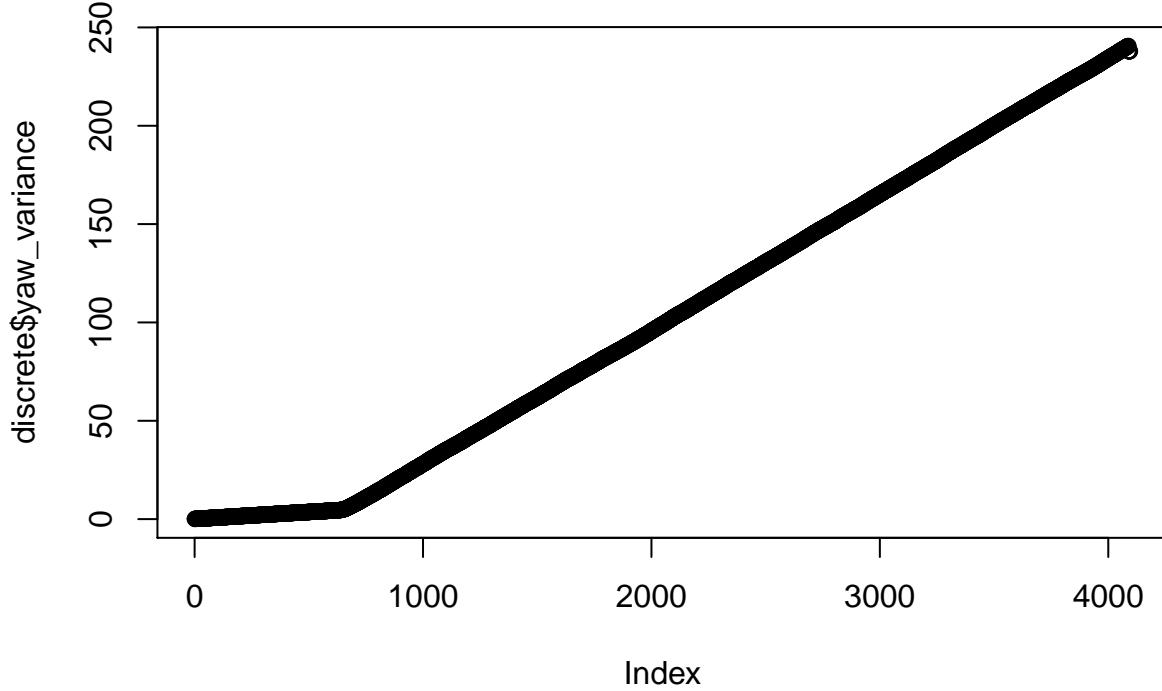
Discrete Filter X Variance Over Time



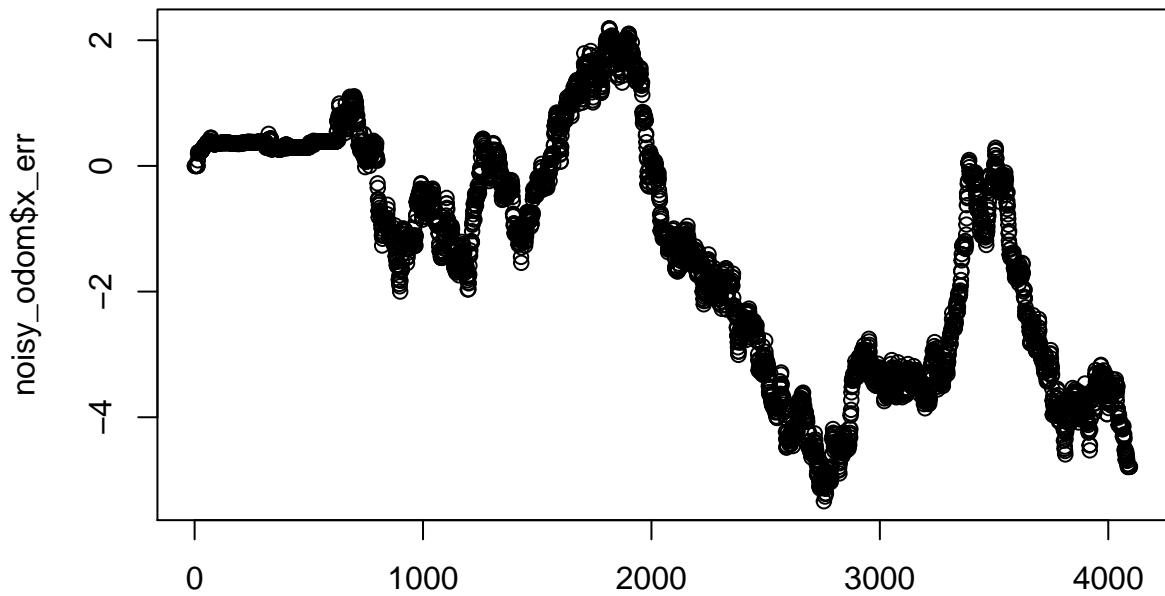
Discrete Filter Y Variance Over Time



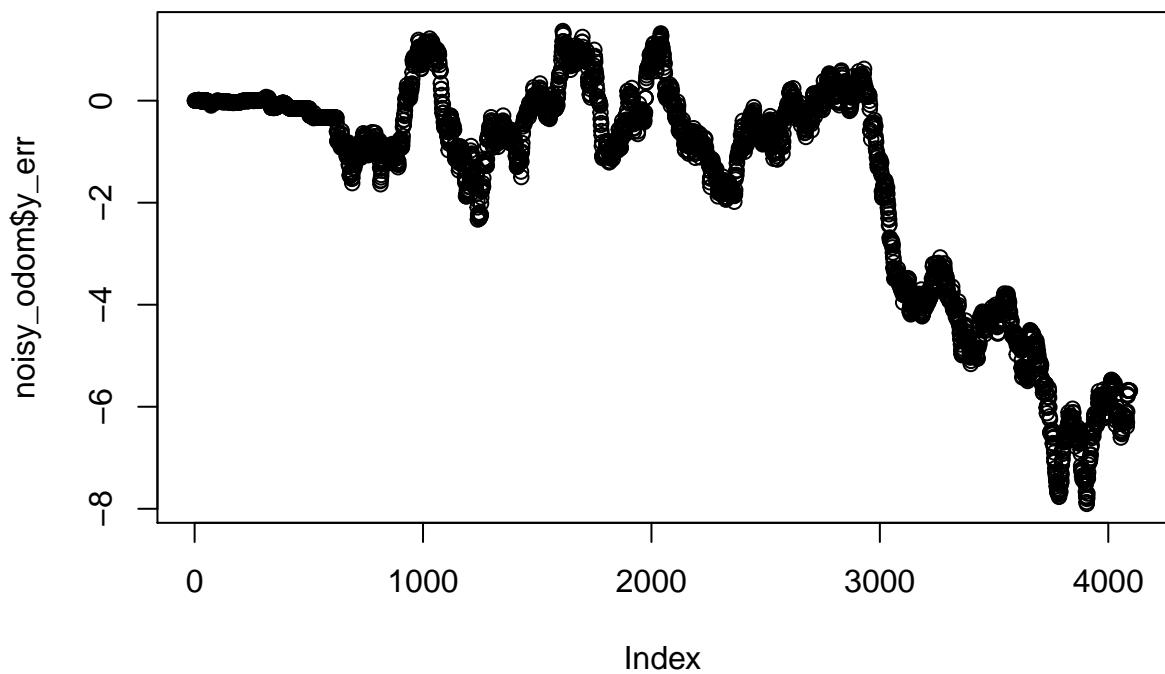
Discrete Filter Yaw Variance Over Time



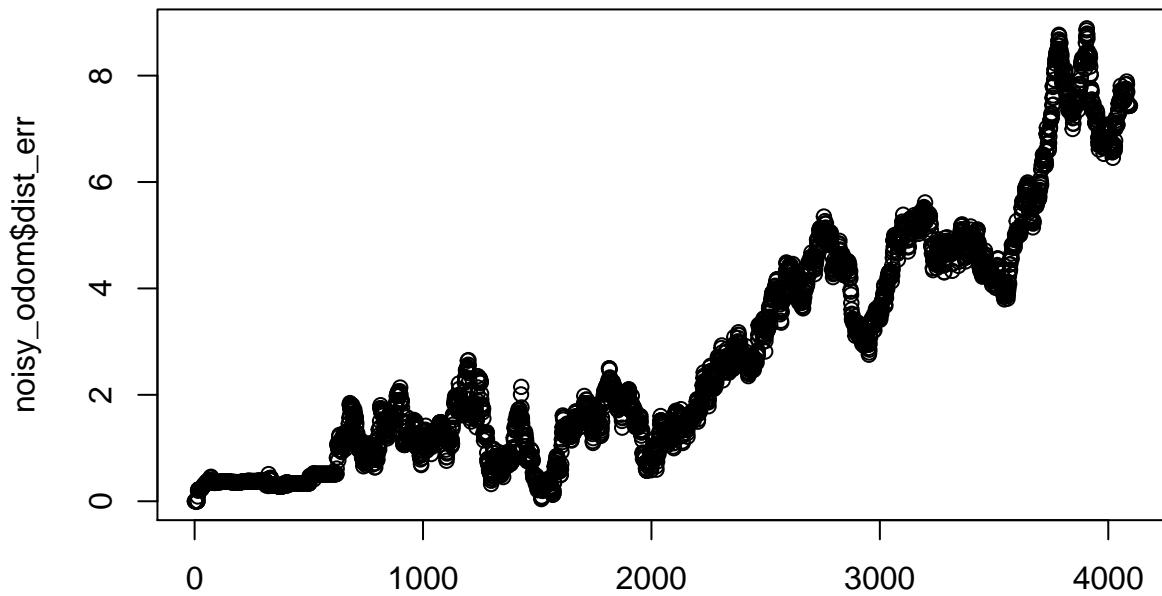
Noisy Odom X Error Over Time



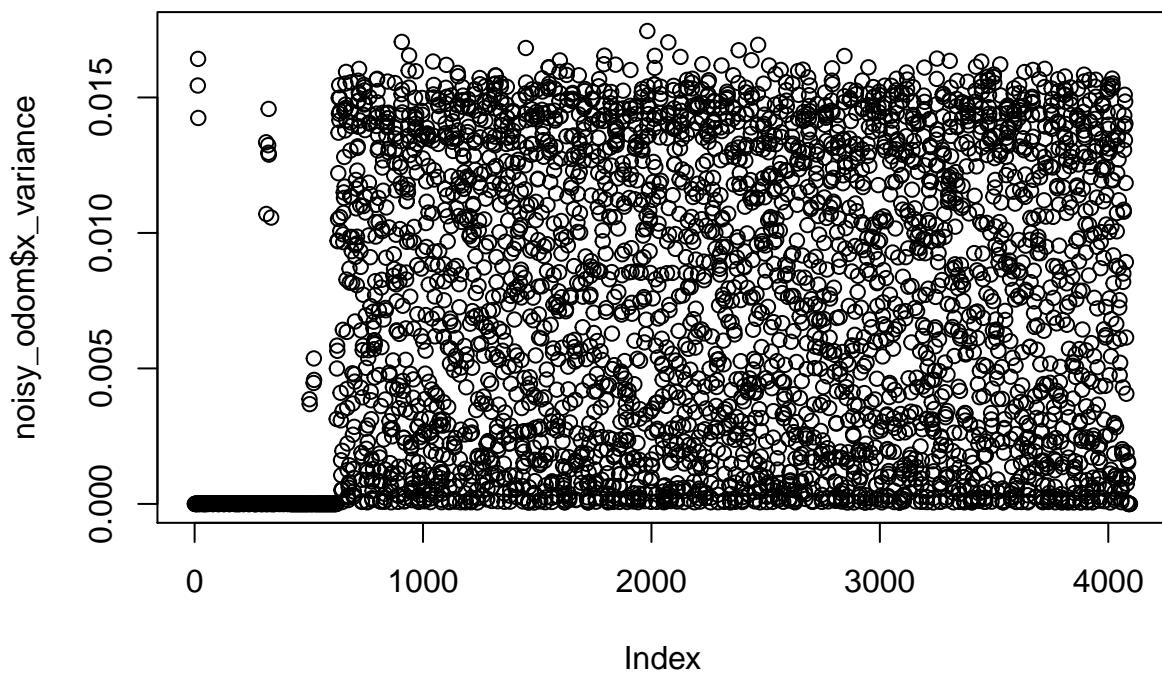
Noisy Odom Y Error Over Time



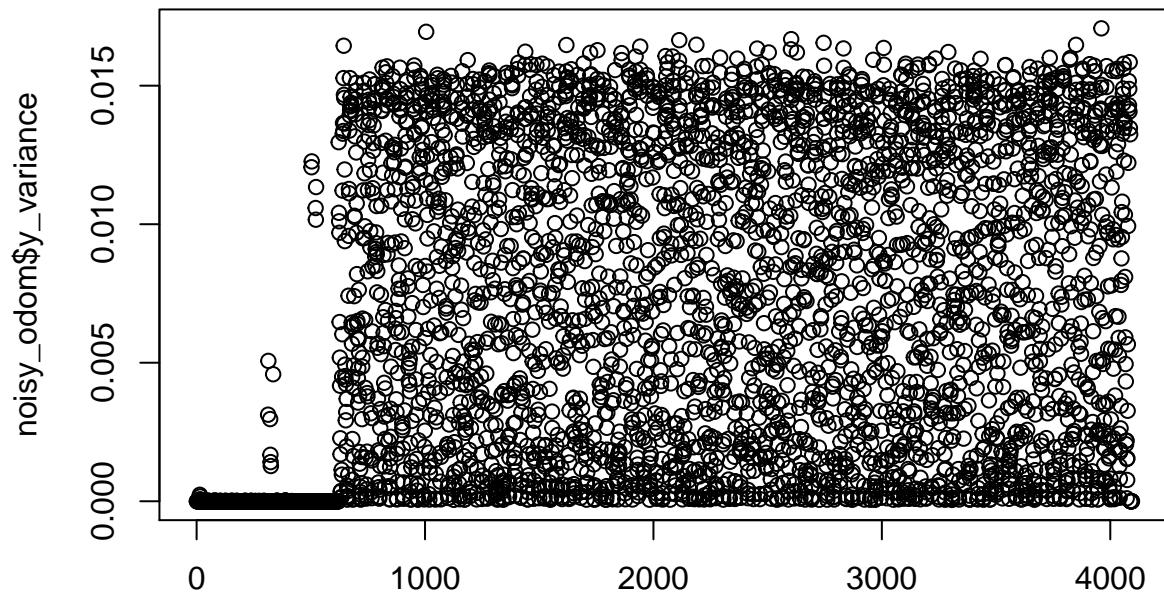
Noisy Odom Horizontal Distance Error Over Time



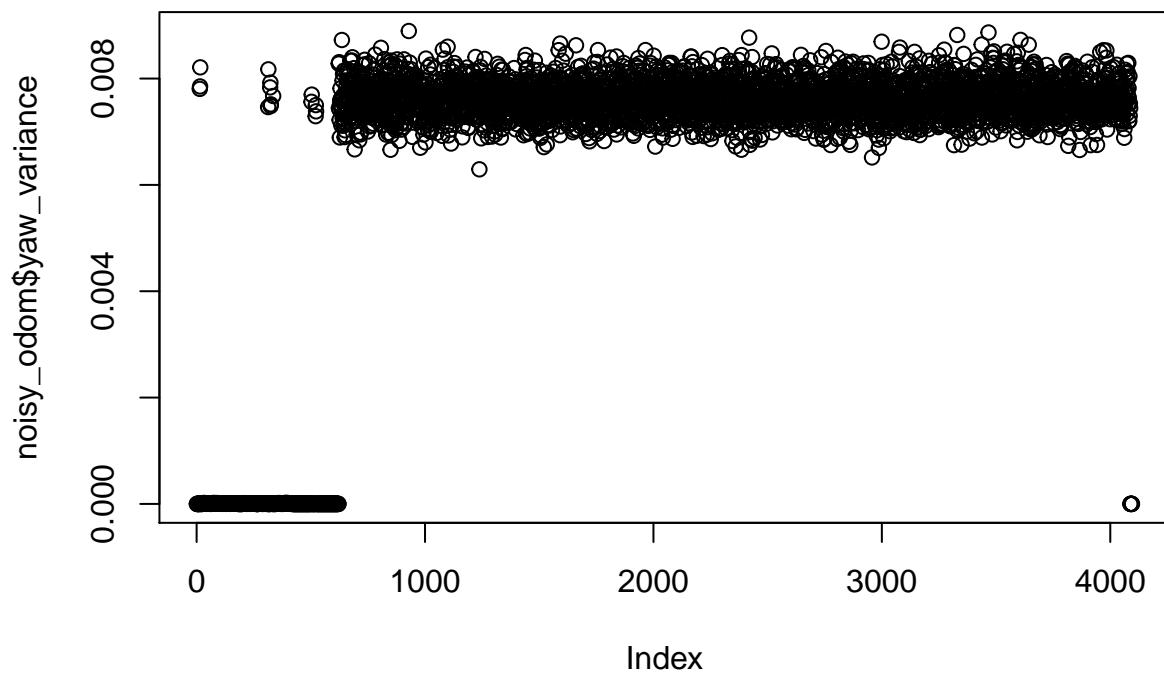
Variance of X Coordinate in Noisy Odometry



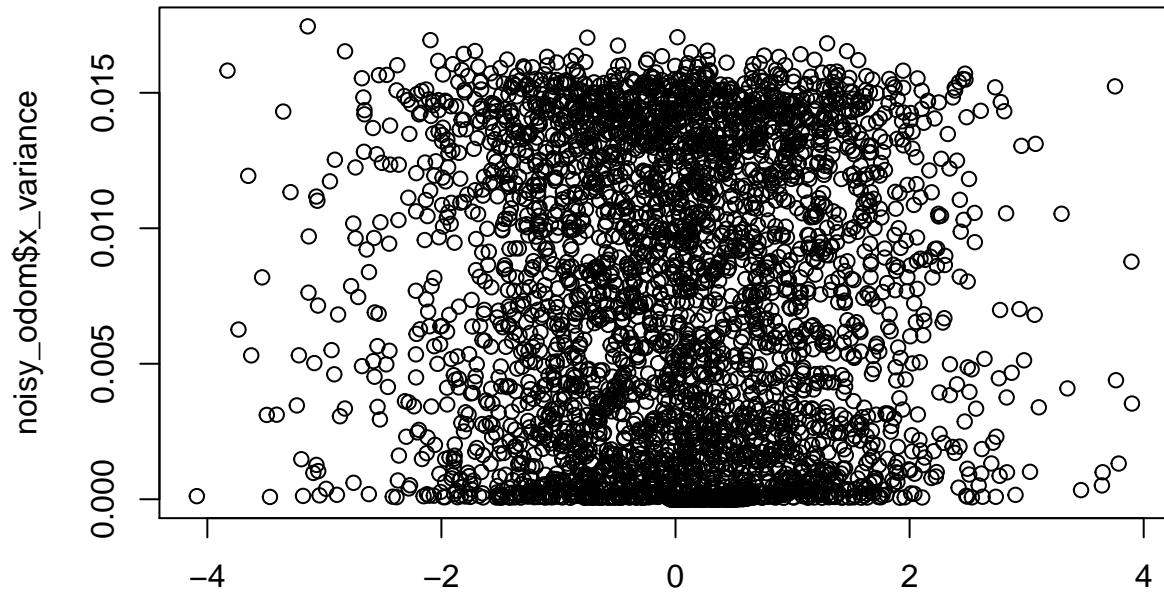
Variance of Y Coordinate in Noisy Odometry



Variance of Yaw Coordinate in Noisy Odometry



Variance vs. Velocity of X in Noisy Odometry



Variance vs. Velocity of Yaw in Noisy Odometry

