

two_stationary Turtlebot 2 Report

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This is a summary of the data from the two_stationary experiment, Turtlebot #2.

The runtime of this experiment was 0 hours, 13 minutes, and 24.1 seconds.

The total number of external pose measurements received by the robot during this time was 7994 which means poses were received at an average of 9.9415496 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.
## 1.514e-05 2.061e-03 4.118e-03 4.114e-03 6.159e-03 8.216e-03

summary(continuous$y_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 8.990e-10 1.500e-06 5.486e-06 7.359e-06 1.235e-05 2.193e-05

summary(continuous$yaw_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 8.598e-05 1.375e-03 2.659e-03 2.673e-03 4.008e-03 5.215e-03

summary(continuous$dist_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 1.514e-05 2.061e-03 4.118e-03 4.114e-03 6.159e-03 8.216e-03

summary(discrete$x_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## -1.81500 -0.41800 -0.01809 -0.03111  0.21810  1.34000

summary(discrete$y_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## -1.813000 -0.304800  0.003646  0.010870  0.328200  1.754000

summary(discrete$yaw_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## -3.776e-05 1.212e-05 2.950e-05 3.304e-05 4.968e-05 1.978e-04

summary(discrete$dist_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 0.02064 0.34350 0.58700 0.71750 1.05900 2.56600

summary(noisy_odom$x_err)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## -3.072e-05 -2.171e-05 -3.194e-06 -6.505e-06 6.250e-06 1.820e-05
```

```

summary(noisy_odom$y_err)

##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 2.827e-08 1.263e-07 2.563e-07 2.502e-07 3.970e-07 4.523e-07

summary(noisy_odom$dist_err)

##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 2.793e-07 5.544e-06 1.403e-05 1.370e-05 2.171e-05 3.072e-05

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

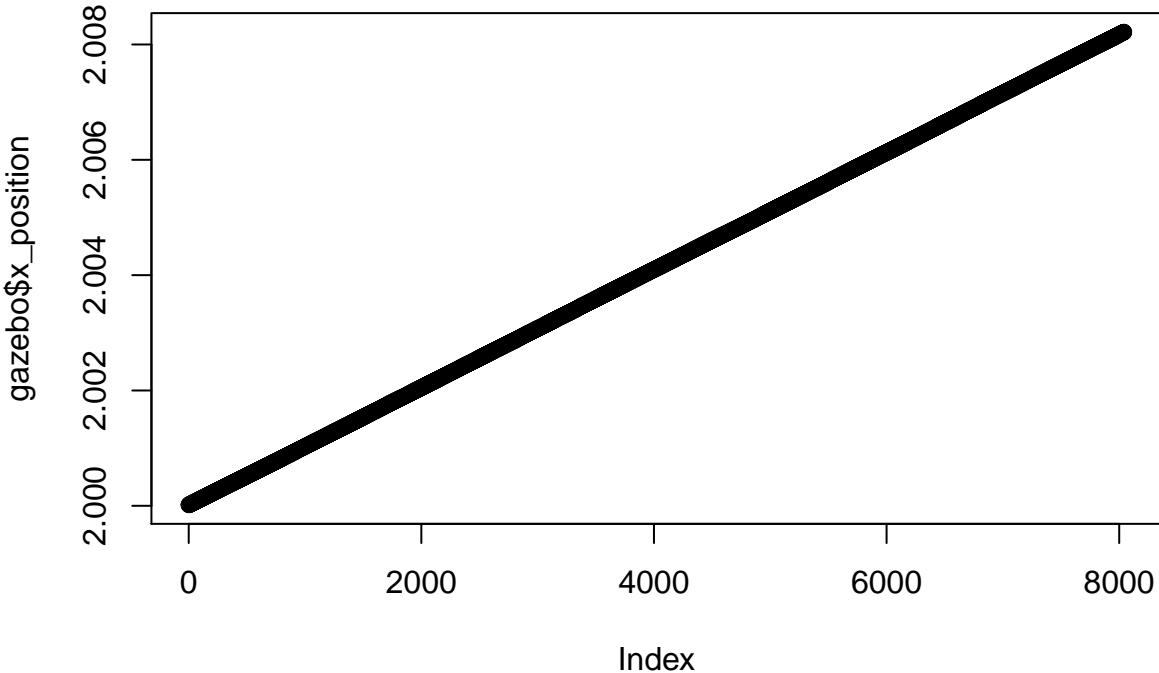
##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 0.3442  1.8530  2.2540  2.3290  2.7730  5.2610

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

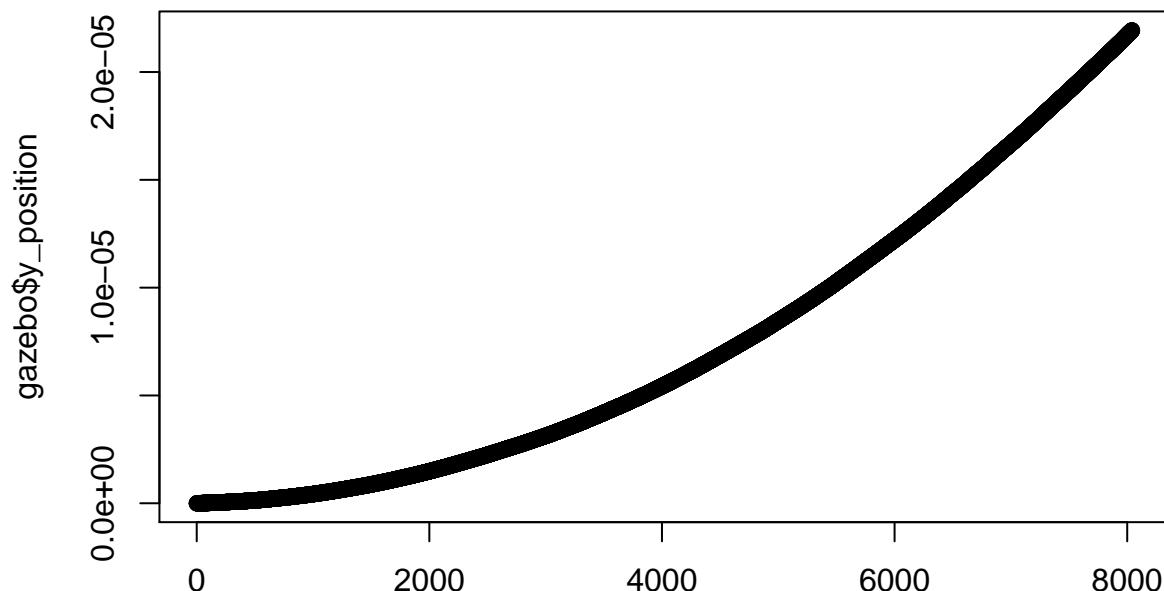
##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 6.692e-16 8.787e-15 1.826e-14 2.386e-14 3.283e-14 2.478e-13

```

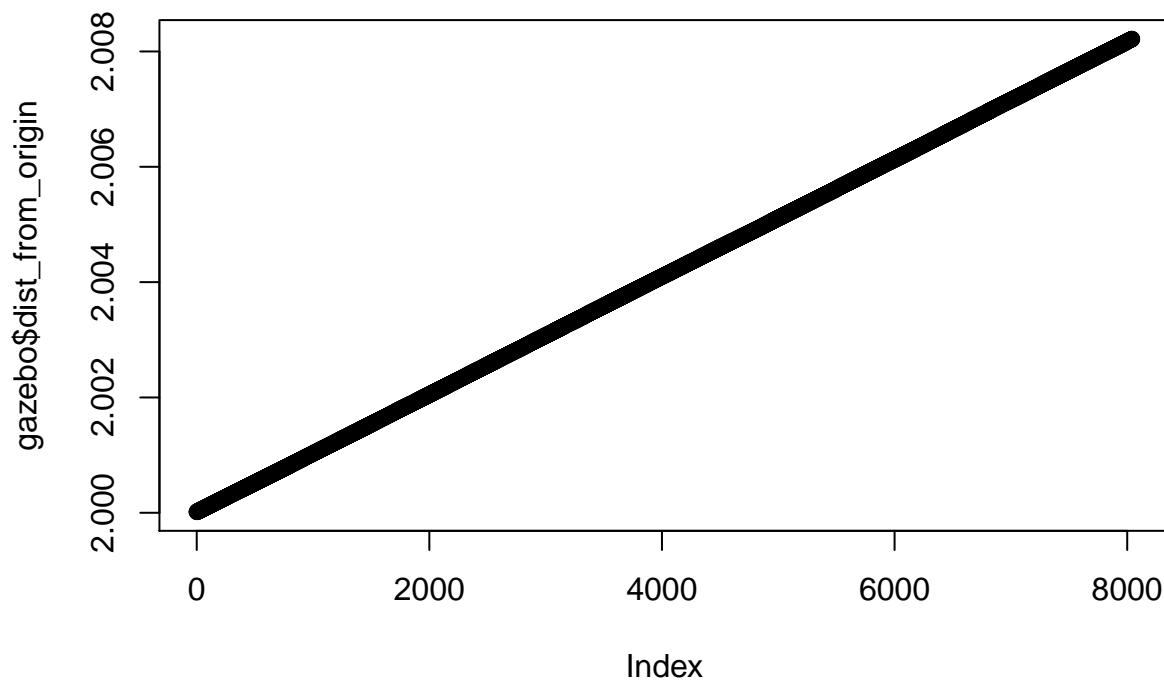
X coordinate of robot over time



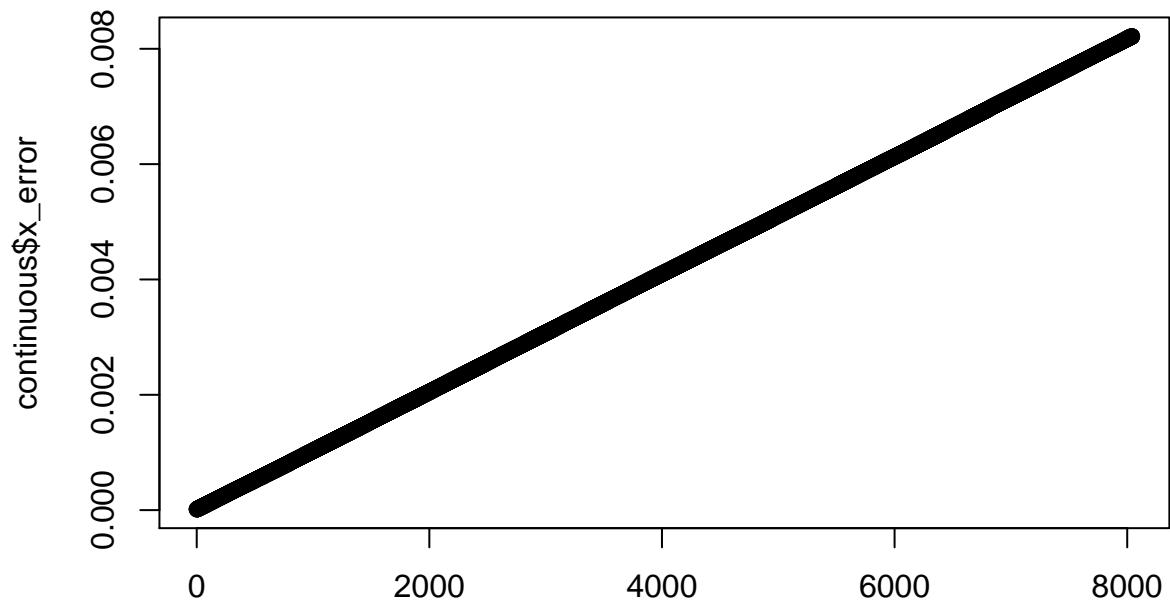
Y coordinate of robot over time



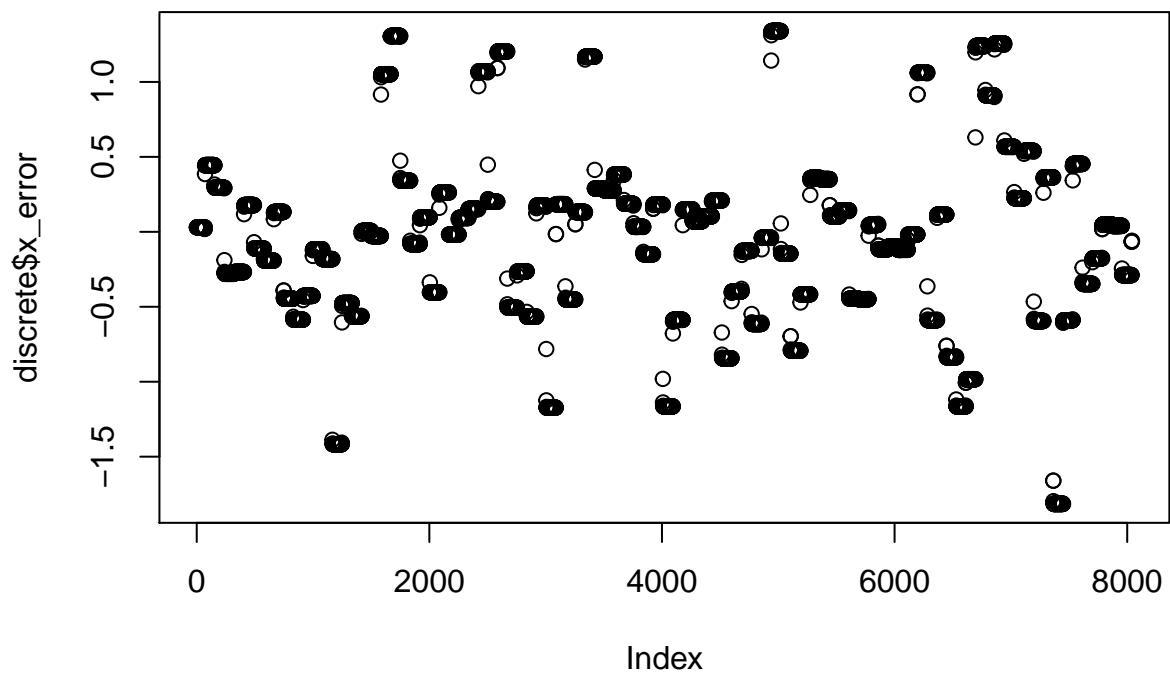
Distance from origin vs. time^{Index}



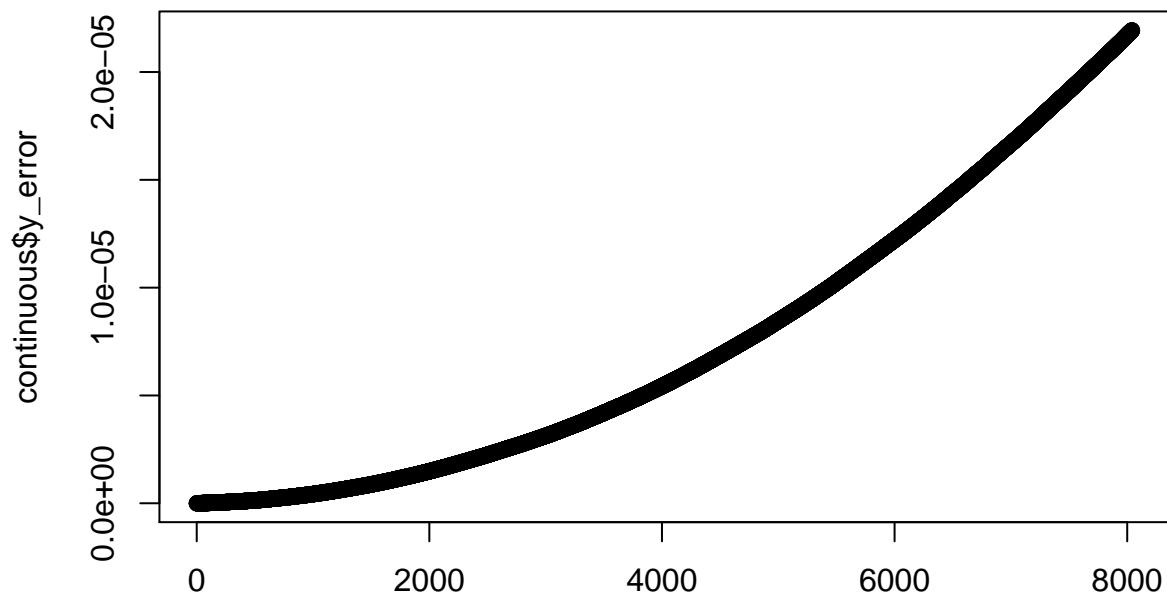
Continuous x_error over time



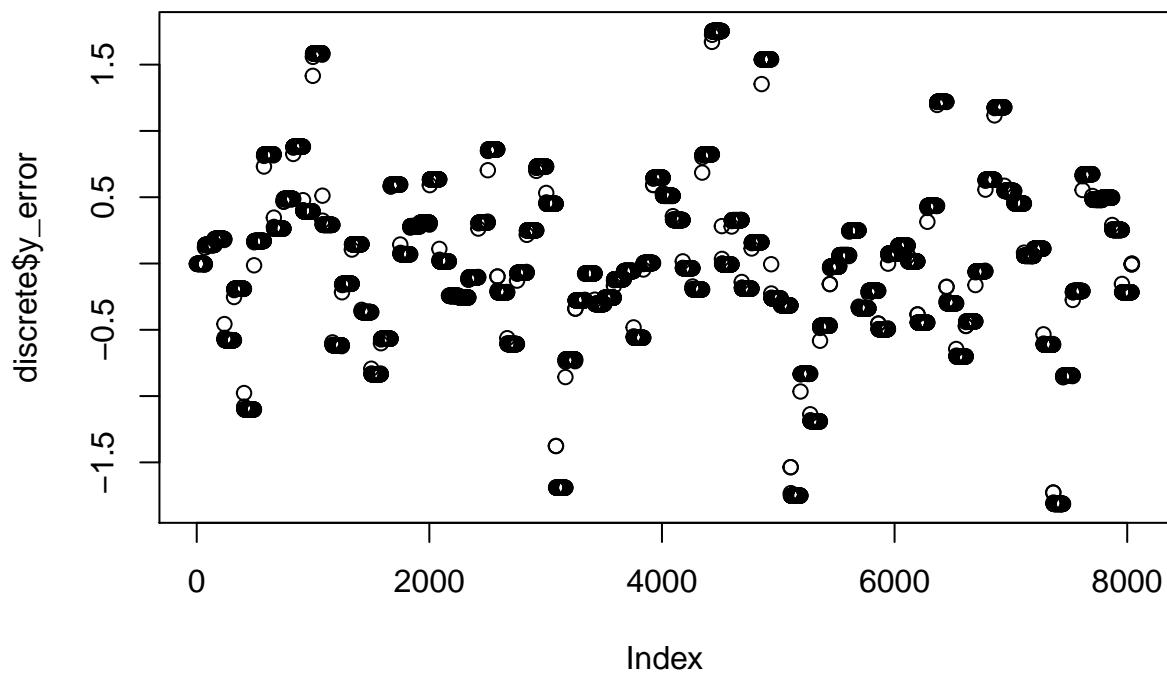
Discrete x_error over time



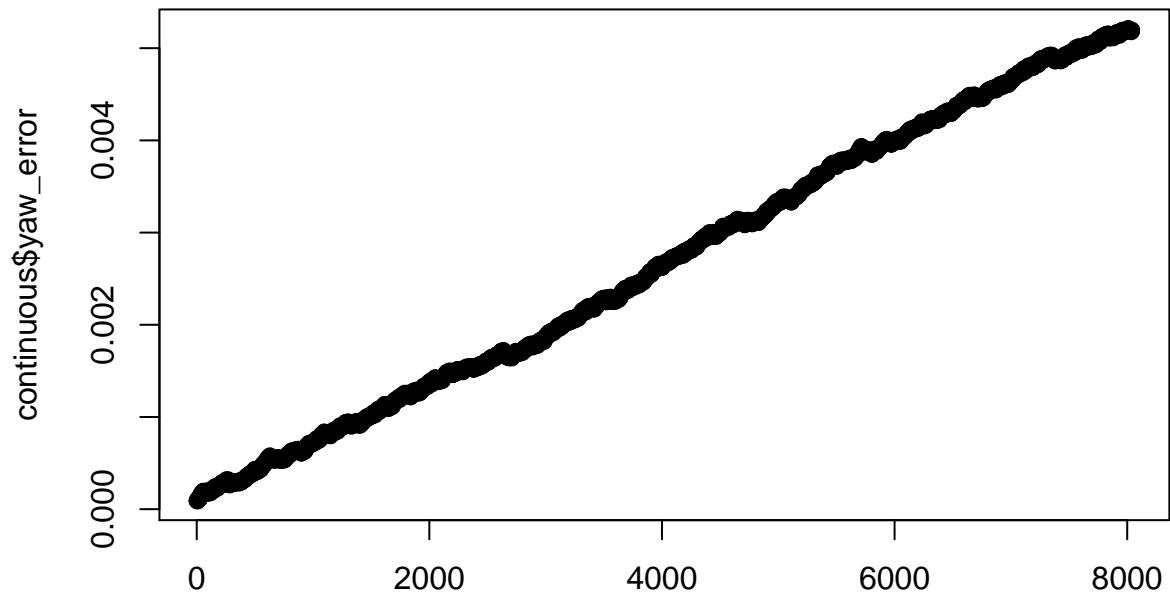
Continuous y_error over time



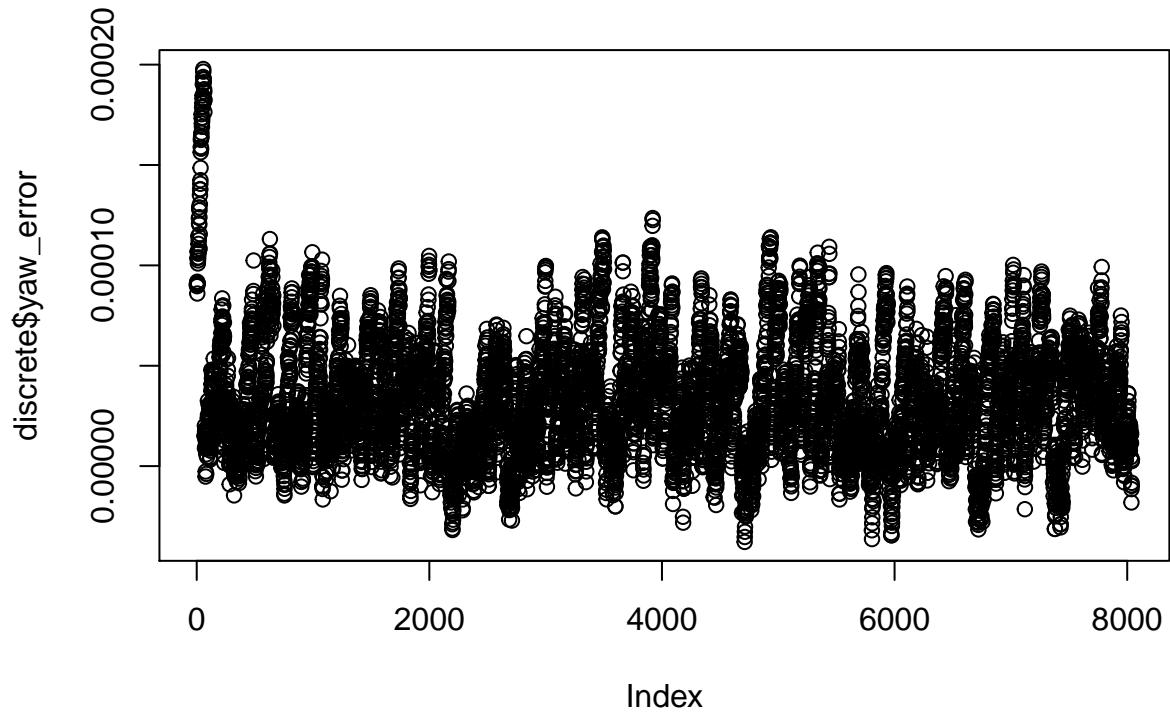
Discrete y_error over time



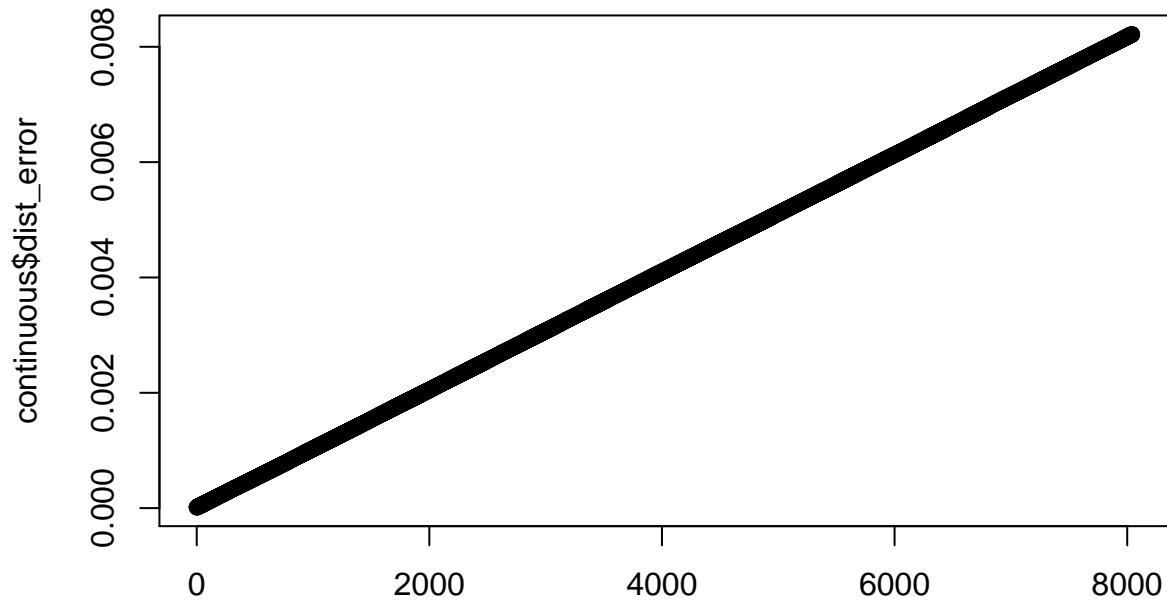
Continuous yaw error over time



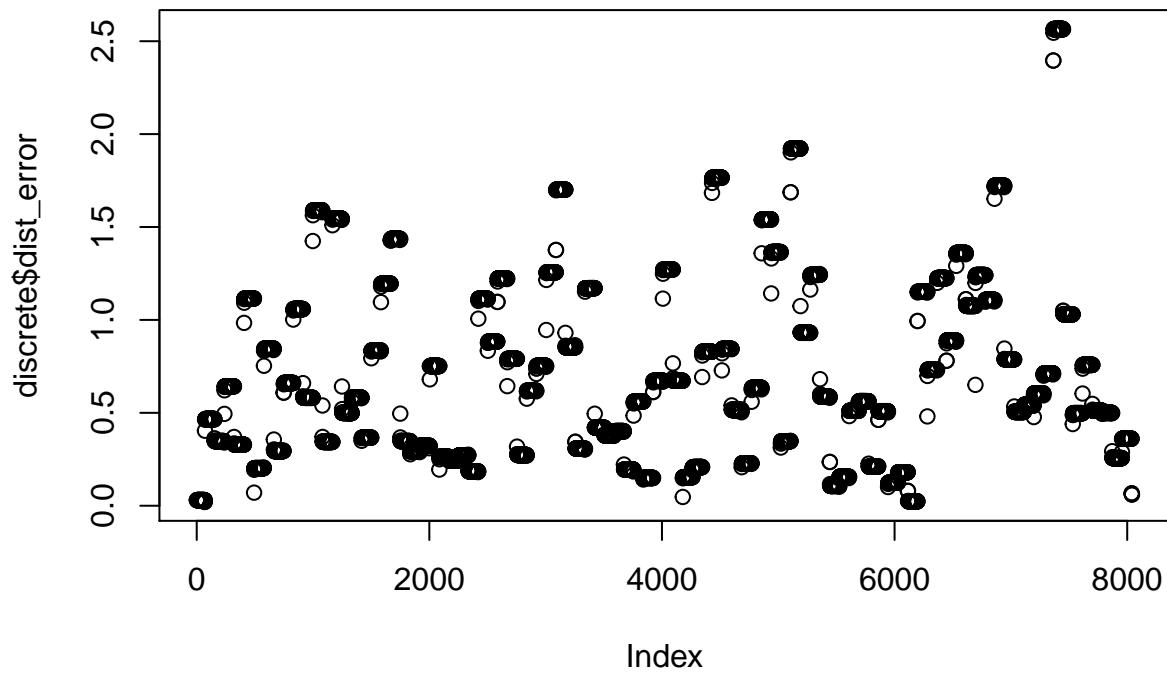
Discrete yaw error over time



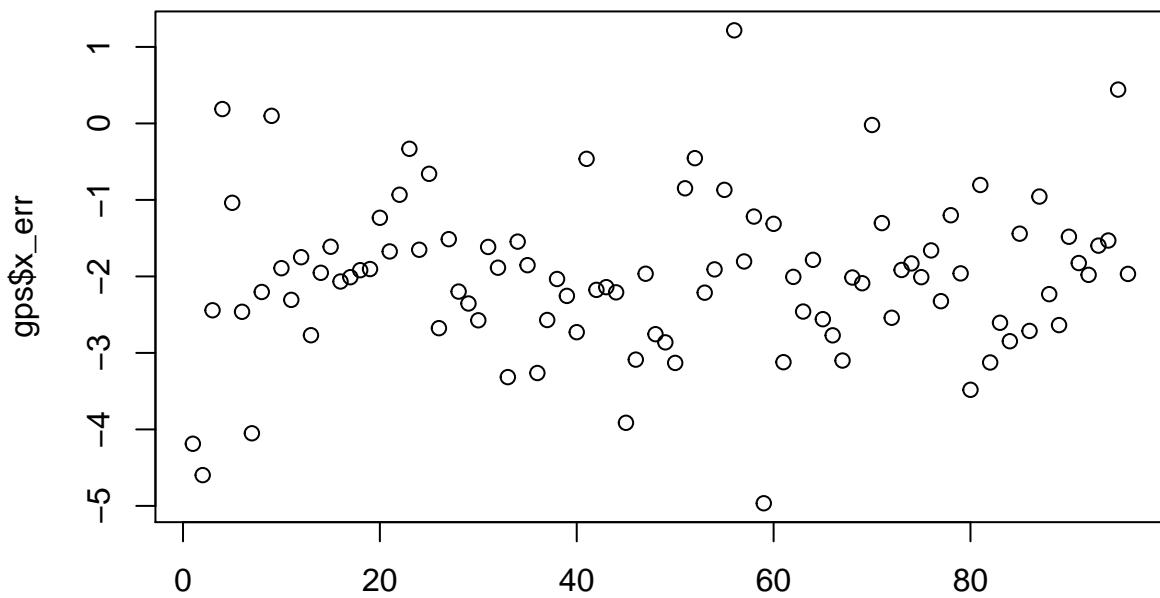
Continuous total distance error over time



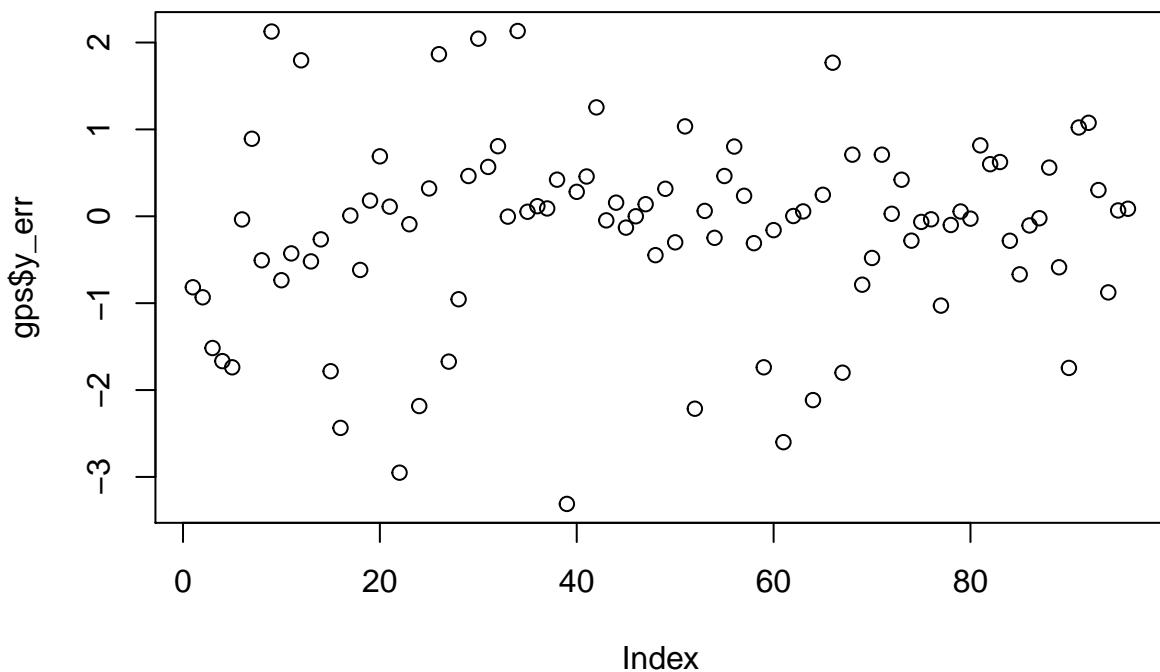
Discrete total distance error over time



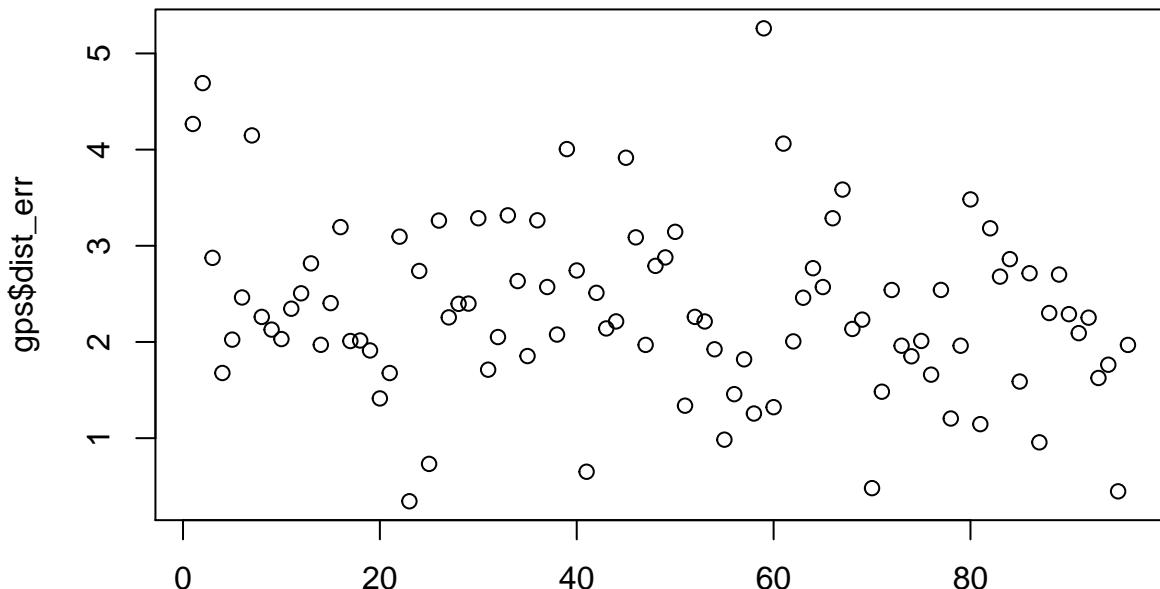
GPS X Error Over Time



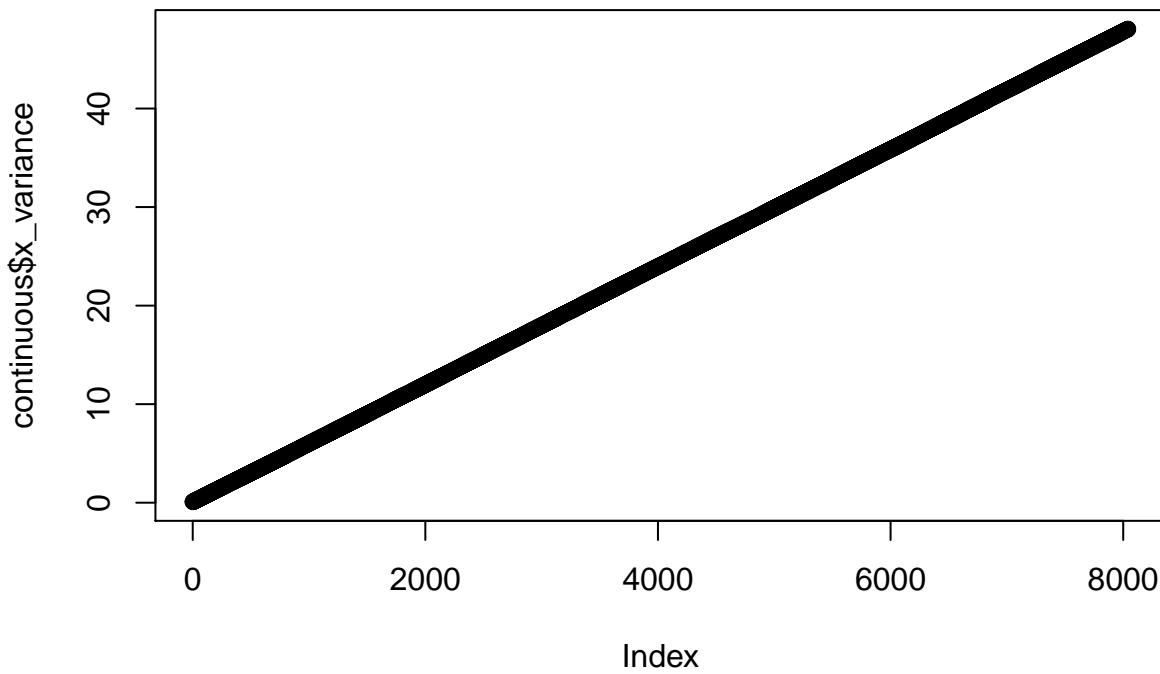
GPS Y Error Over Time



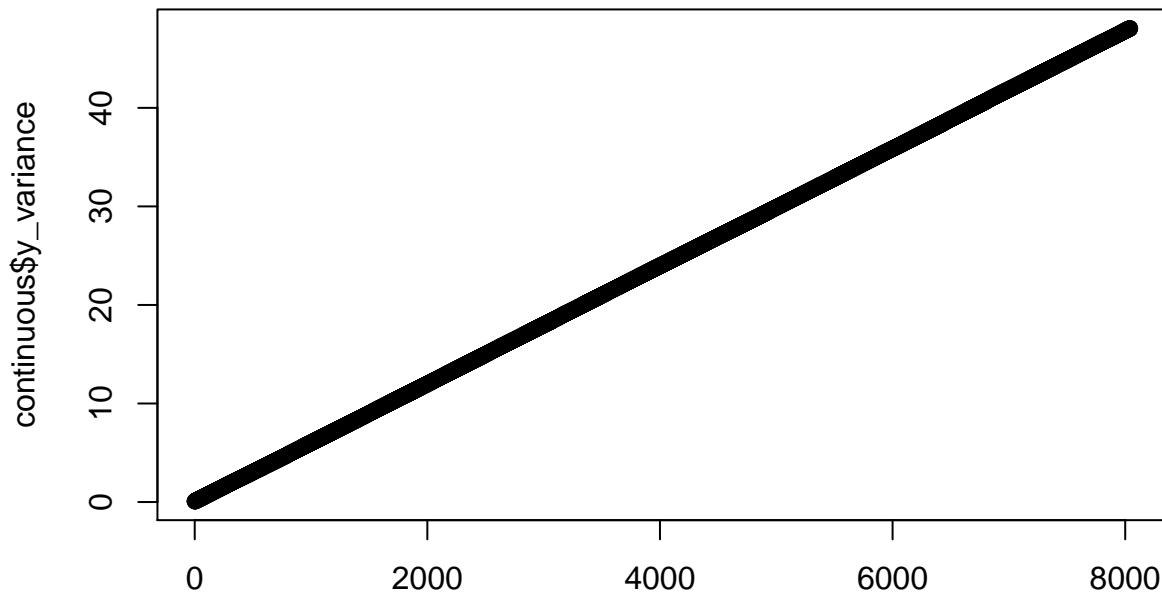
GPS Horizontal Distance Error Over Time



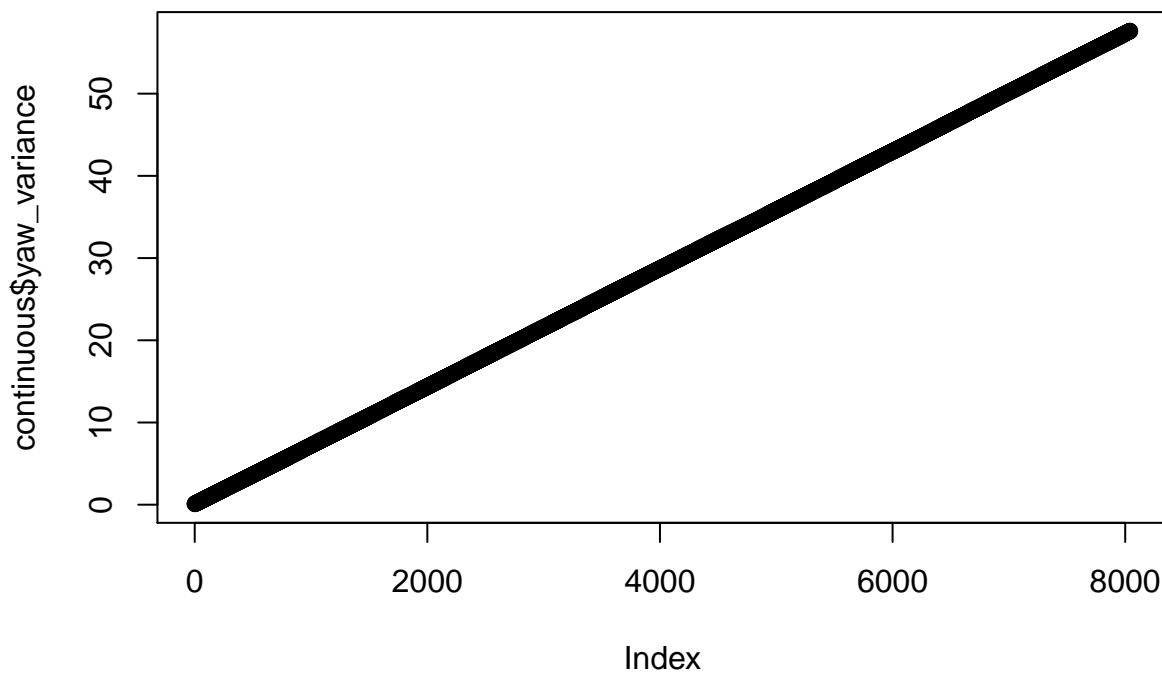
Continuous Filter X Variance Over Time



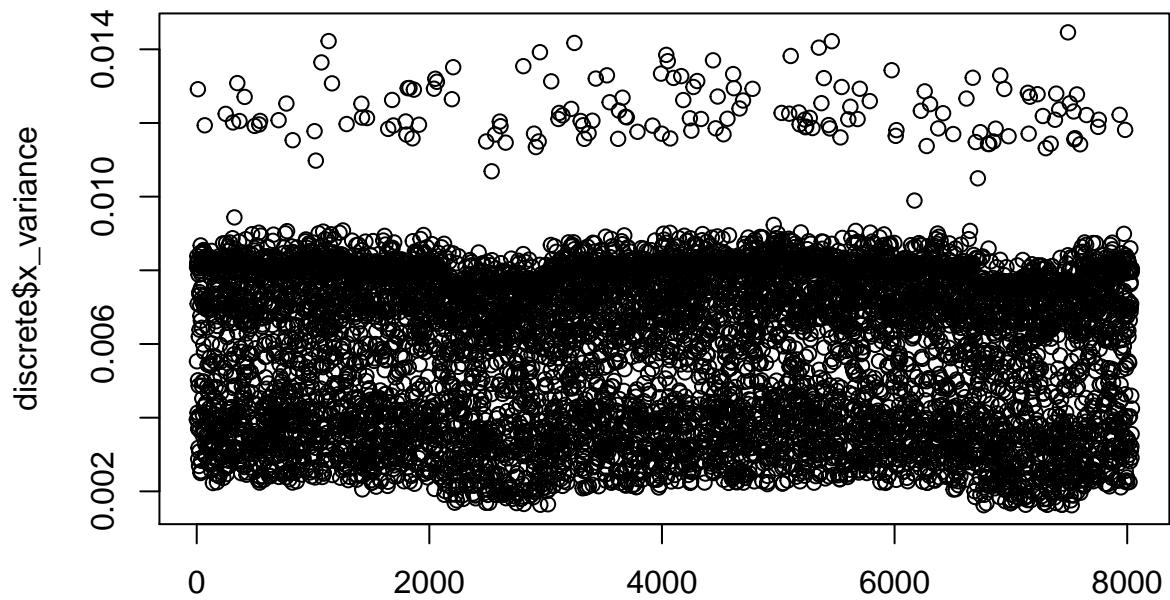
Continuous Filter Y Variance Over Time



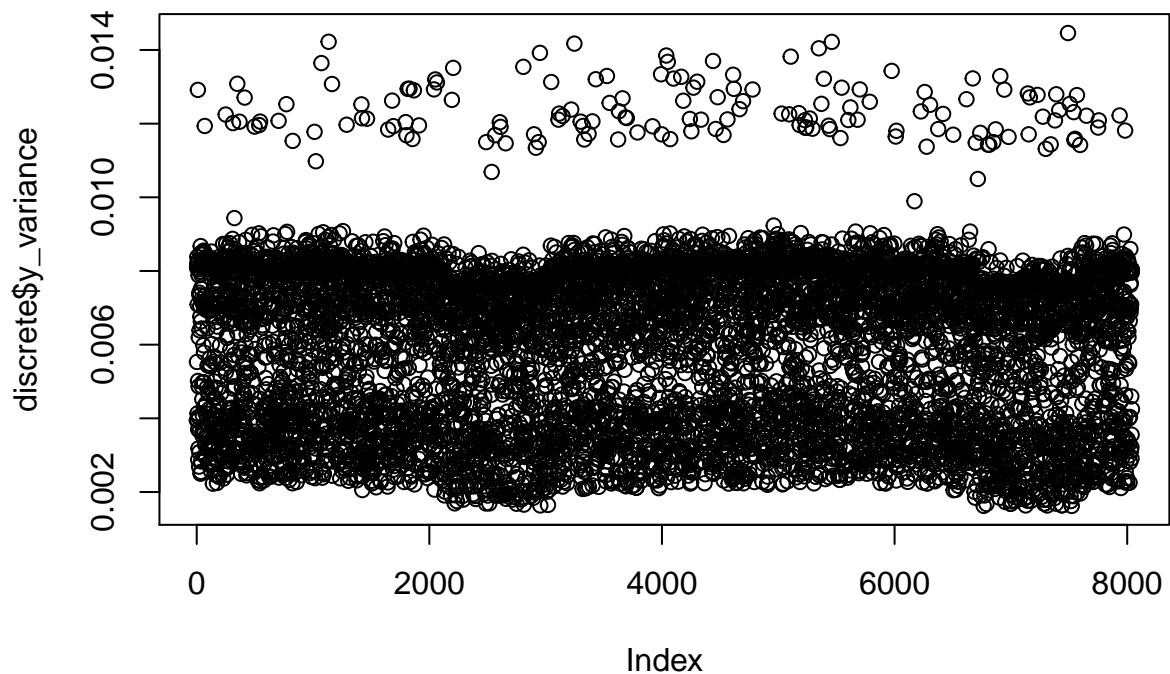
Continuous Filter Yaw Variance Over Time



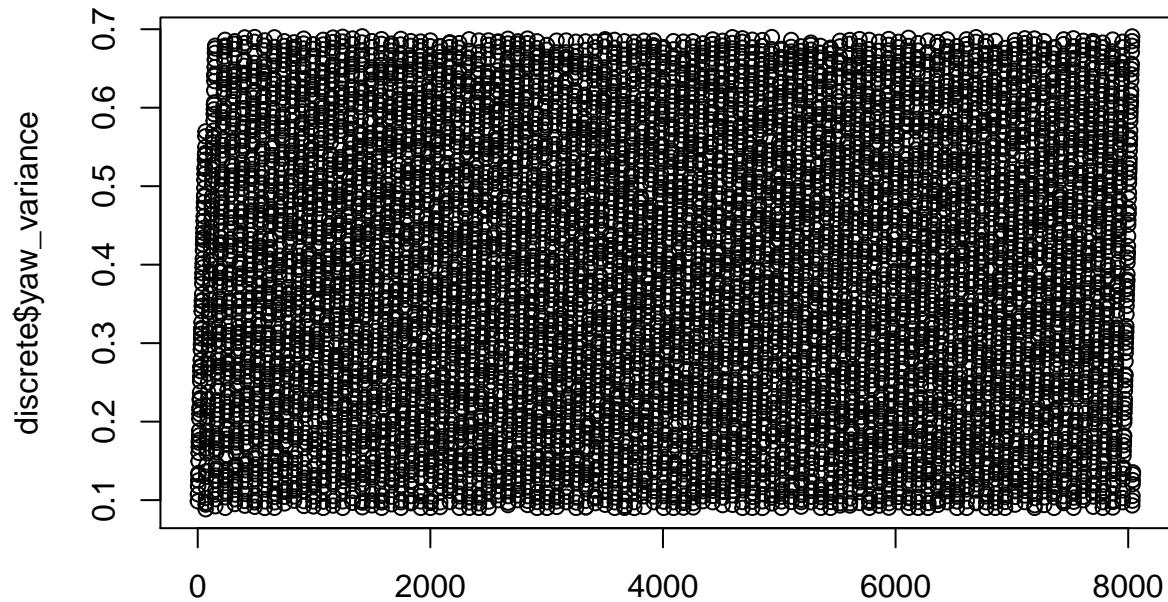
Discrete Filter X Variance Over Time



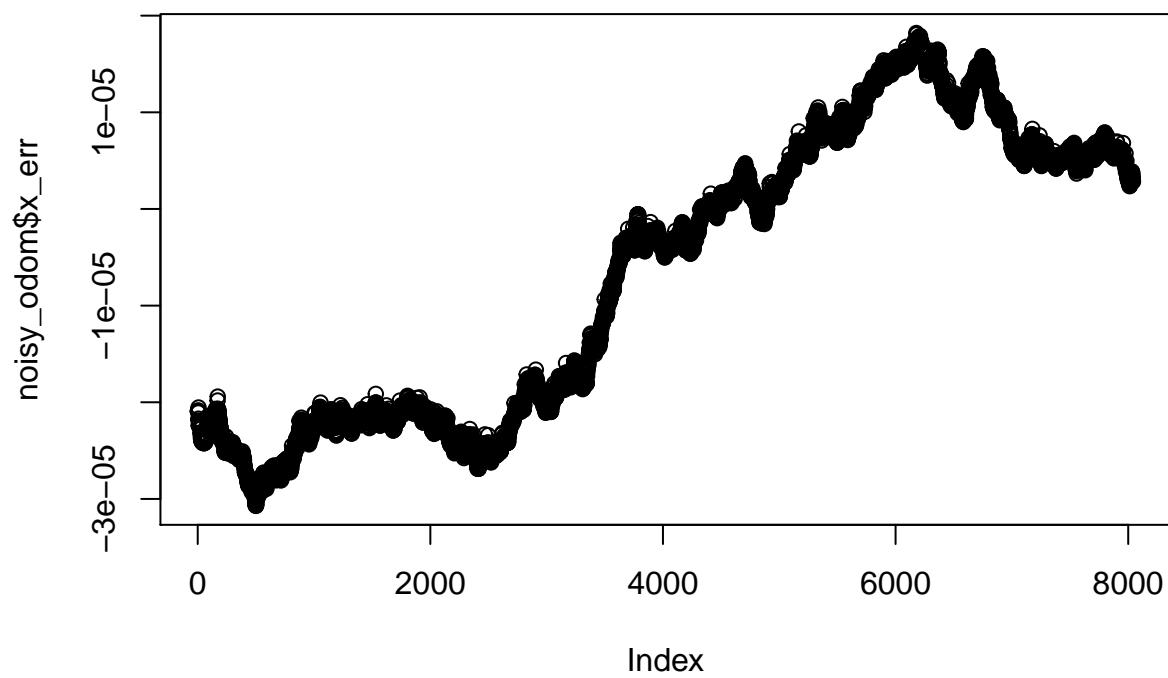
Discrete Filter Y Variance Over Time



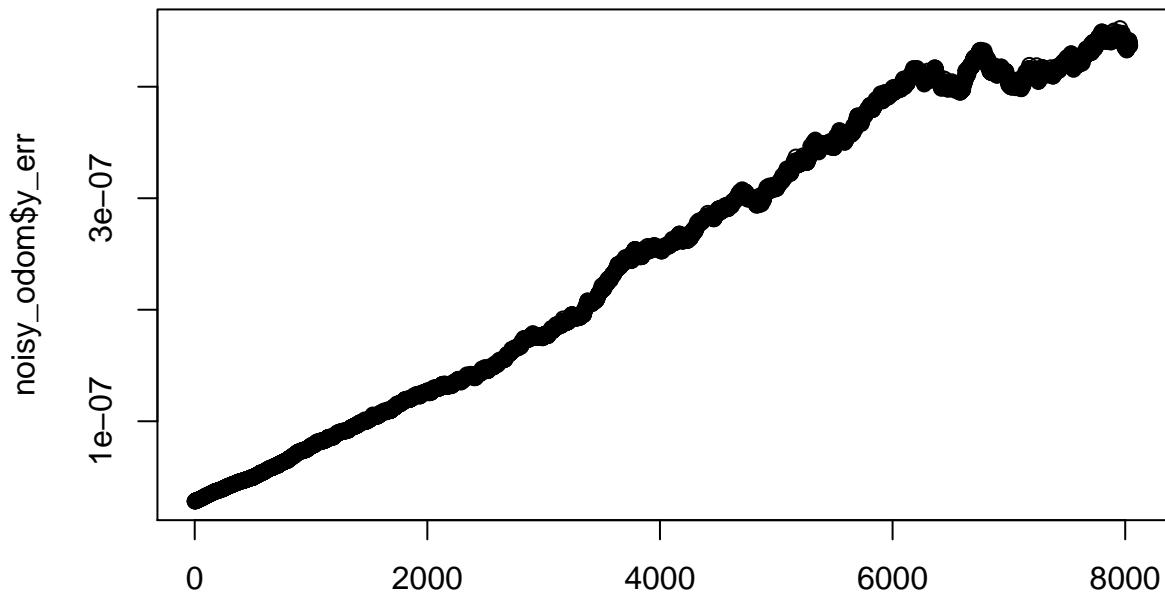
Discrete Filter Yaw Variance Over Time



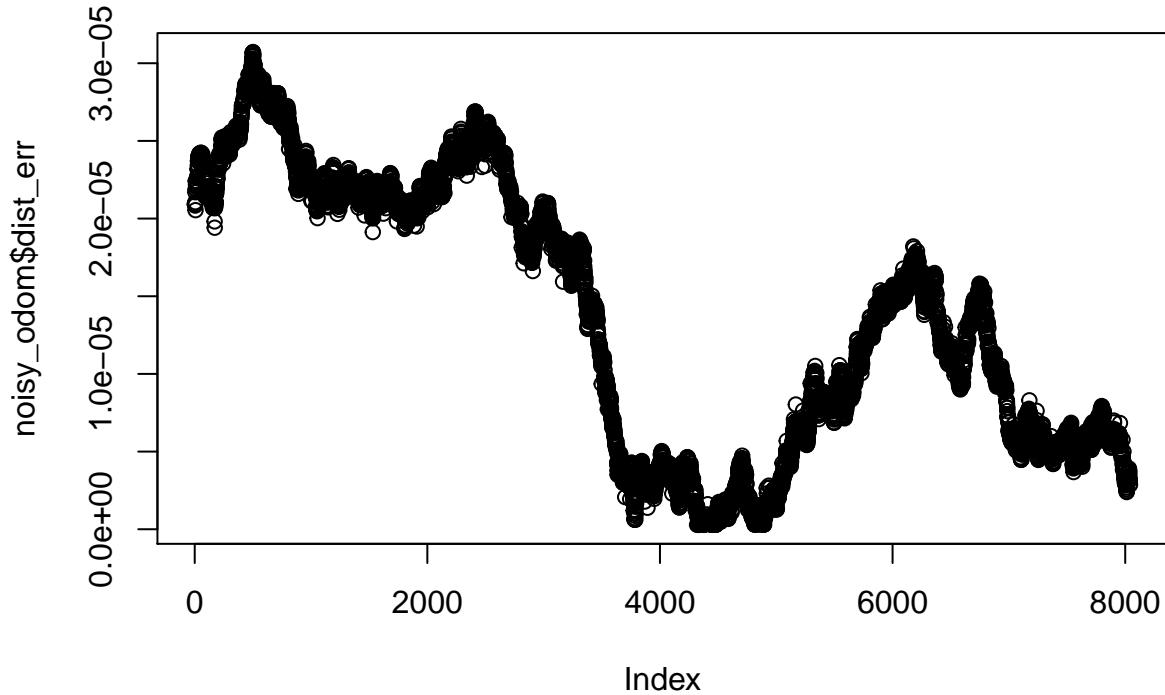
Noisy Odom X Error Over Time



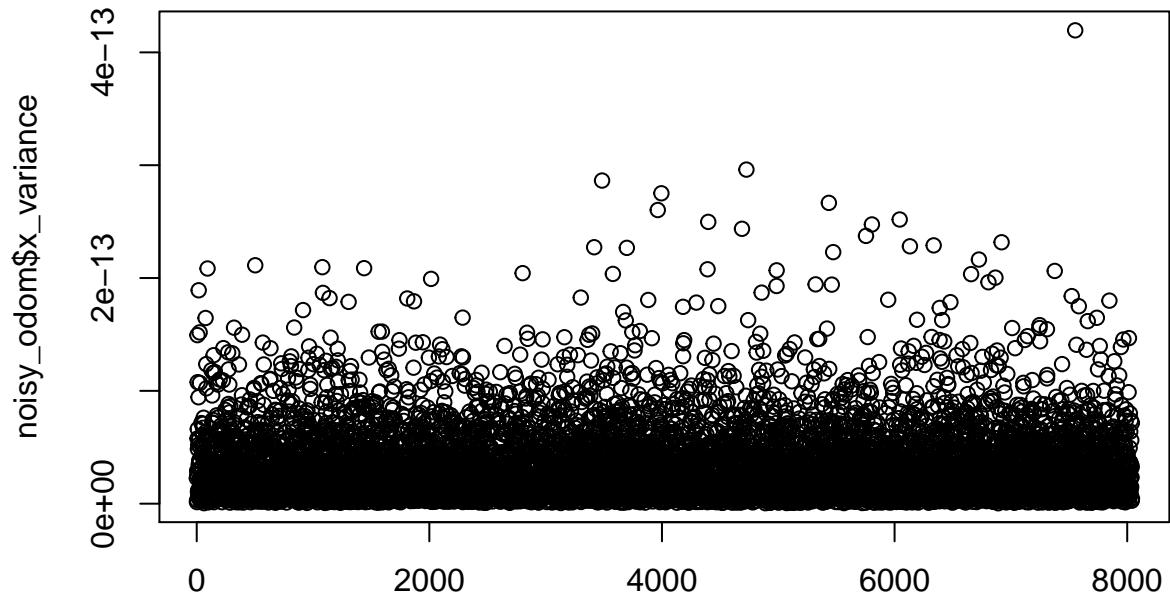
Noisy Odom Y Error Over Time



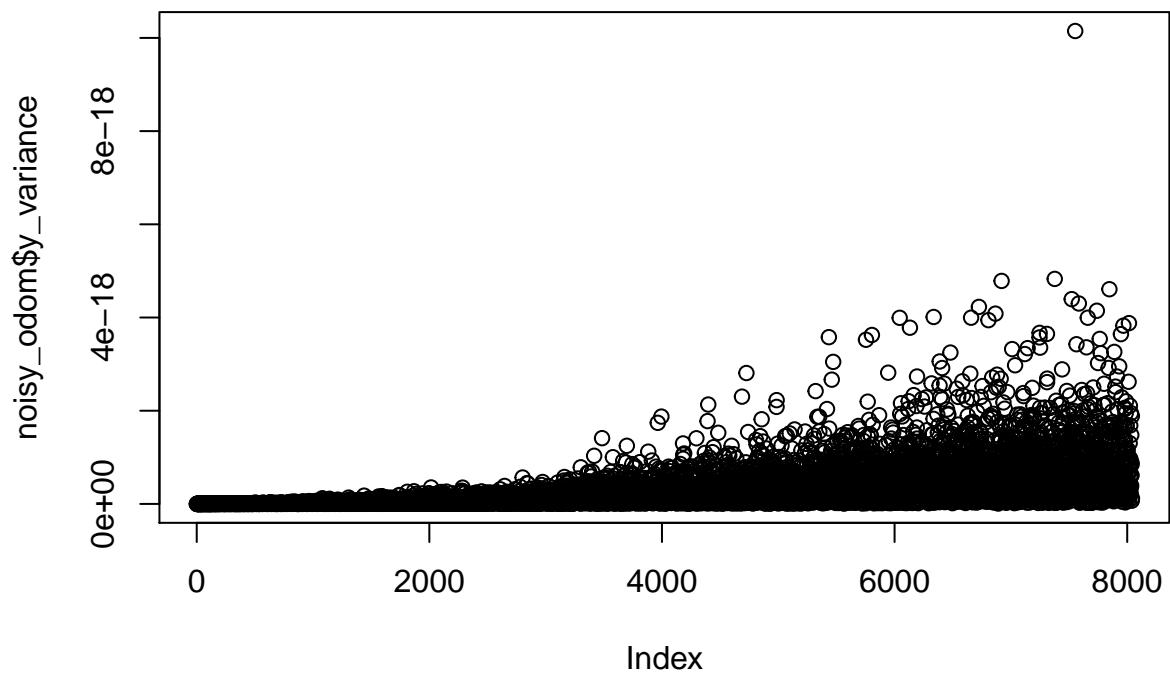
Noisy Odom Horizontal Distance Error Over Time



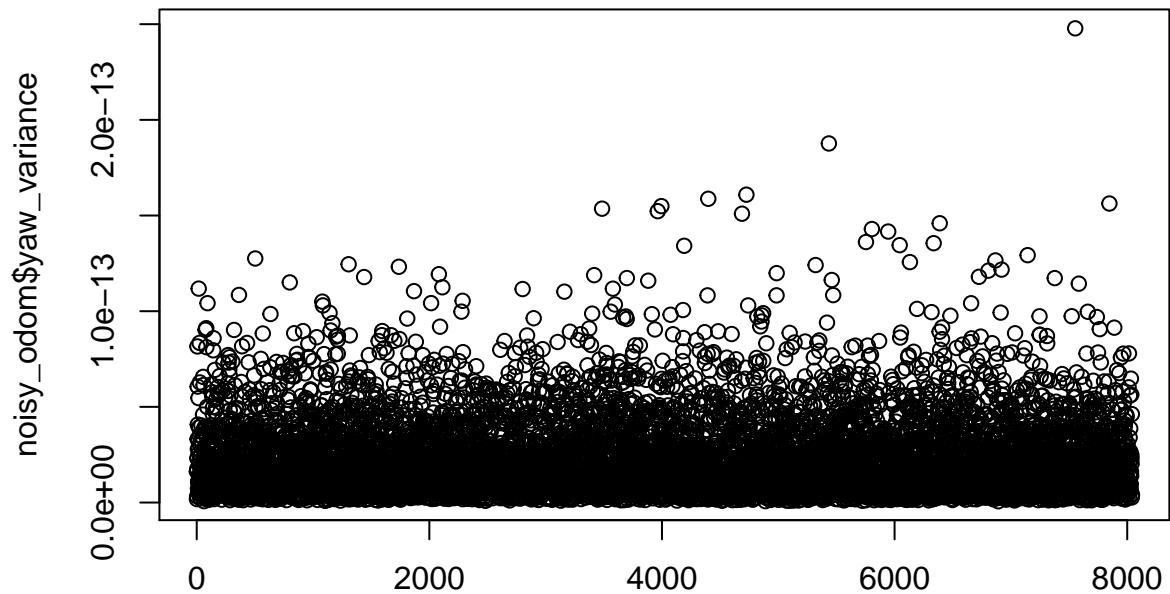
Variance of X Coordinate in Noisy Odometry



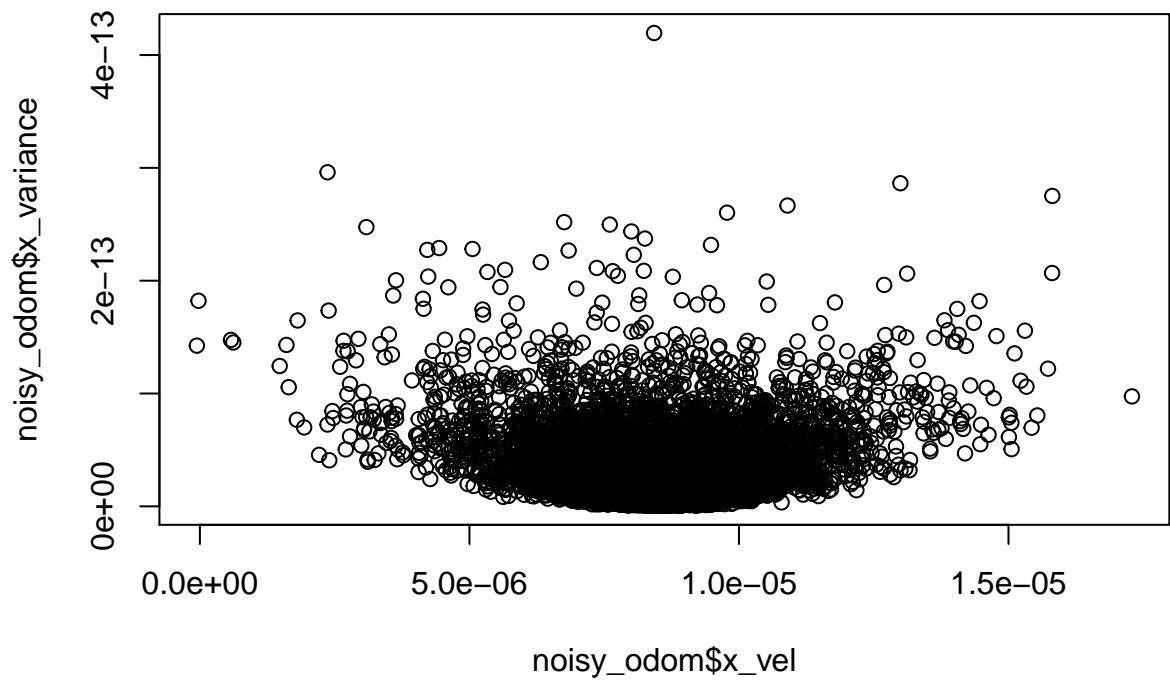
Variance of Y Coordinate in Noisy Odometry



Variance of Yaw Coordinate in Noisy Odometry



Variance vs. Velocity of X in Noisy Odometry



Variance vs. Velocity of Yaw in Noisy Odometry

