

two_stationary_noiseless Turtlebot 2 Report

Matthew Swartwout

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

The runtime of this experiment was 0 hours, 12 minutes, and 57 seconds.

The total number of external pose measurements received by the robot during this time was 7988 which means poses were received at an average of 10.2805663 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.
## 1.352e-05 2.069e-03 4.133e-03 4.120e-03 6.170e-03 8.214e-03

summary(continuous$y_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 6.710e-10 1.978e-06 7.197e-06 9.213e-06 1.544e-05 2.645e-05

summary(continuous$yaw_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 6.838e-05 1.783e-03 3.316e-03 3.230e-03 4.693e-03 6.114e-03

summary(continuous$dist_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## 1.352e-05 2.069e-03 4.133e-03 4.120e-03 6.170e-03 8.214e-03

summary(discrete$x_error)

##      Min.    1st Qu.     Median      Mean 3rd Qu.      Max.
## 0.02778 0.03021 0.03025 0.03024 0.03028 0.03033

summary(discrete$y_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## -0.008177 -0.006879 -0.005825 -0.005650 -0.004361 -0.002643

summary(discrete$yaw_error)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## -4.546e-05 1.106e-05 3.199e-05 3.526e-05 5.597e-05 1.813e-04

summary(discrete$dist_error)

##      Min.    1st Qu.     Median      Mean 3rd Qu.      Max.
## 0.02803 0.03055 0.03078 0.03079 0.03101 0.03140

summary(noisy_odom$x_err)

##      Min.    1st Qu.     Median      Mean    3rd Qu.      Max.
## -2.955e-05 -2.302e-05 -1.752e-05 -1.893e-05 -1.526e-05 -9.555e-06
```

```

summary(noisy_odom$y_err)

##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 6.349e-09 3.933e-08 5.826e-08 6.714e-08 9.776e-08 1.446e-07

summary(noisy_odom$dist_err)

##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 9.555e-06 1.526e-05 1.752e-05 1.893e-05 2.302e-05 2.955e-05

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

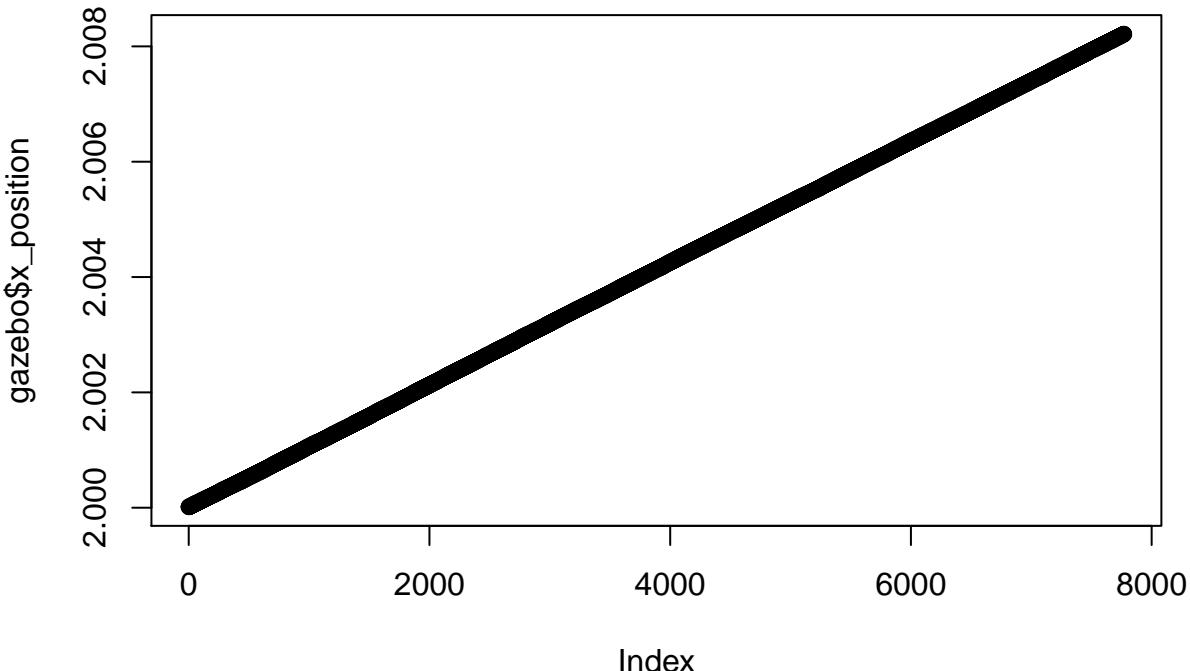
##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 2.000   2.002   2.004   2.004   2.006   2.008

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

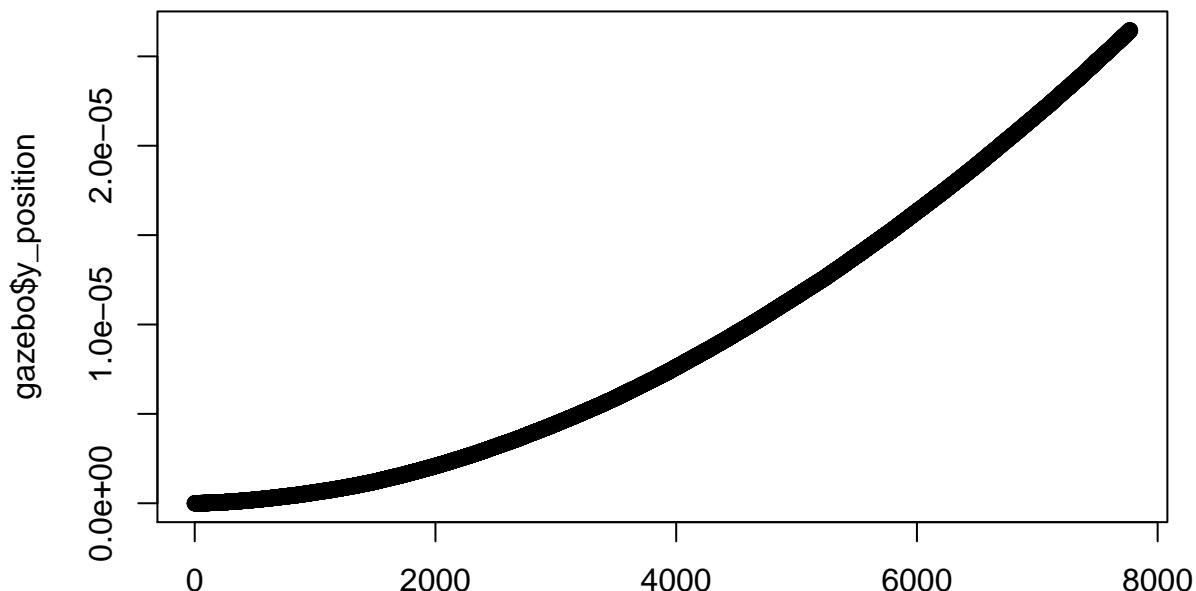
##      Min.   1st Qu.    Median     Mean   3rd Qu.   Max.
## 7.839e-16 8.897e-15 1.824e-14 2.429e-14 3.314e-14 2.355e-13

```

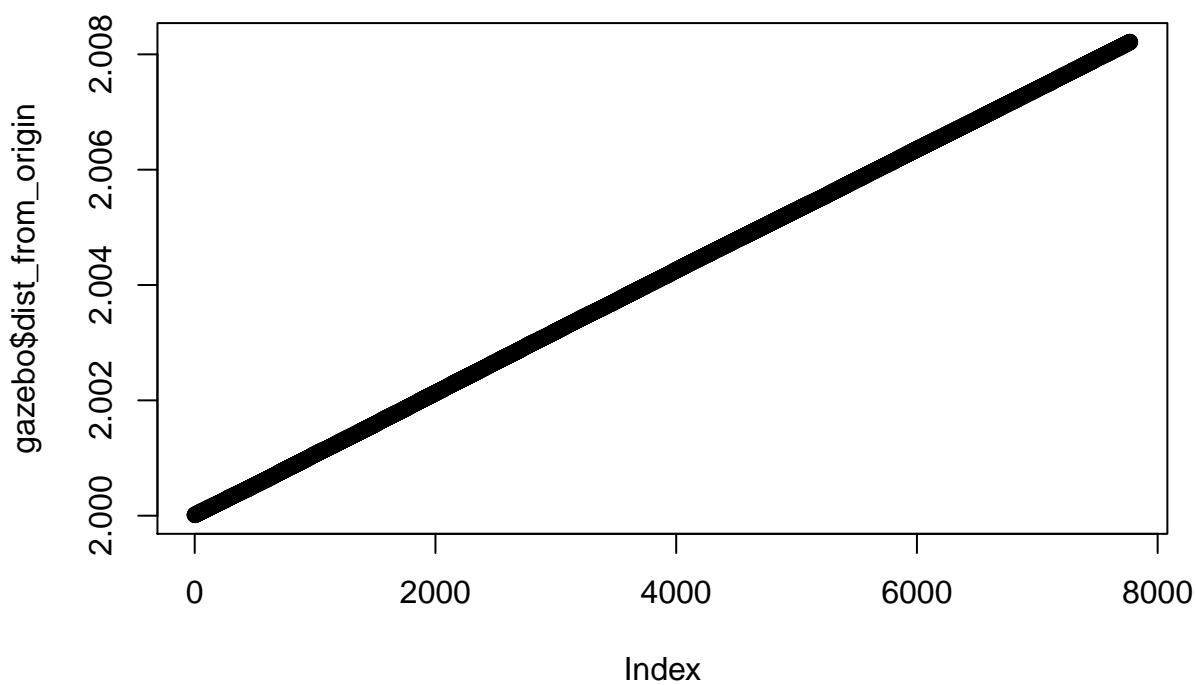
X coordinate of robot over time



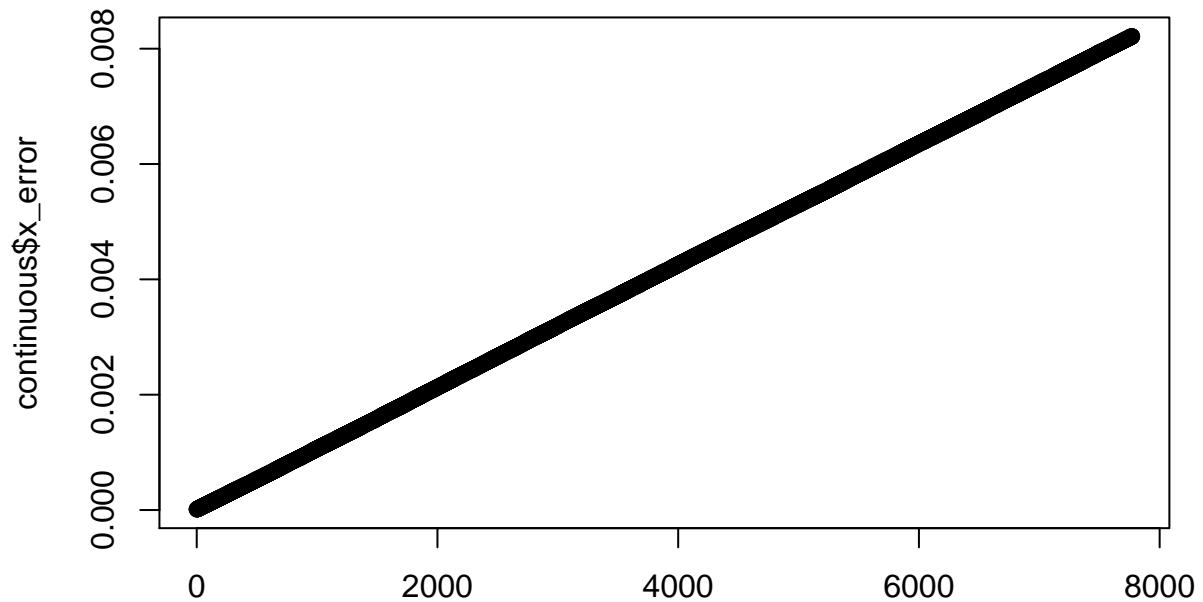
Y coordinate of robot over time



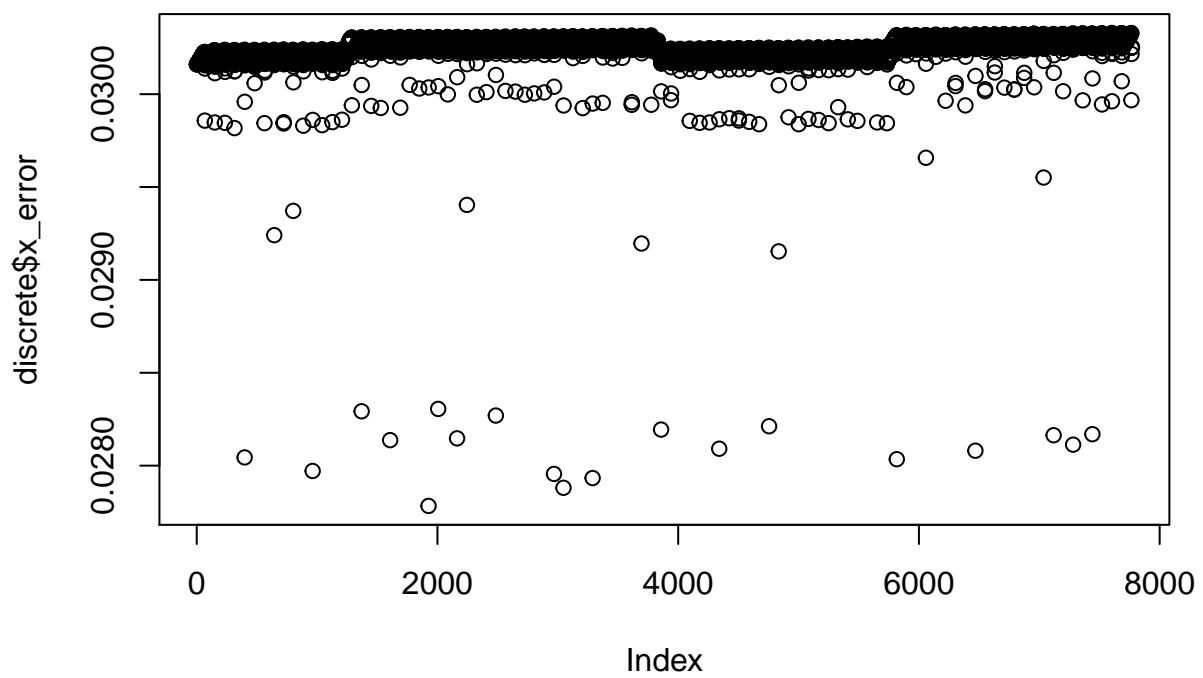
Distance from origin vs. time^{Index}



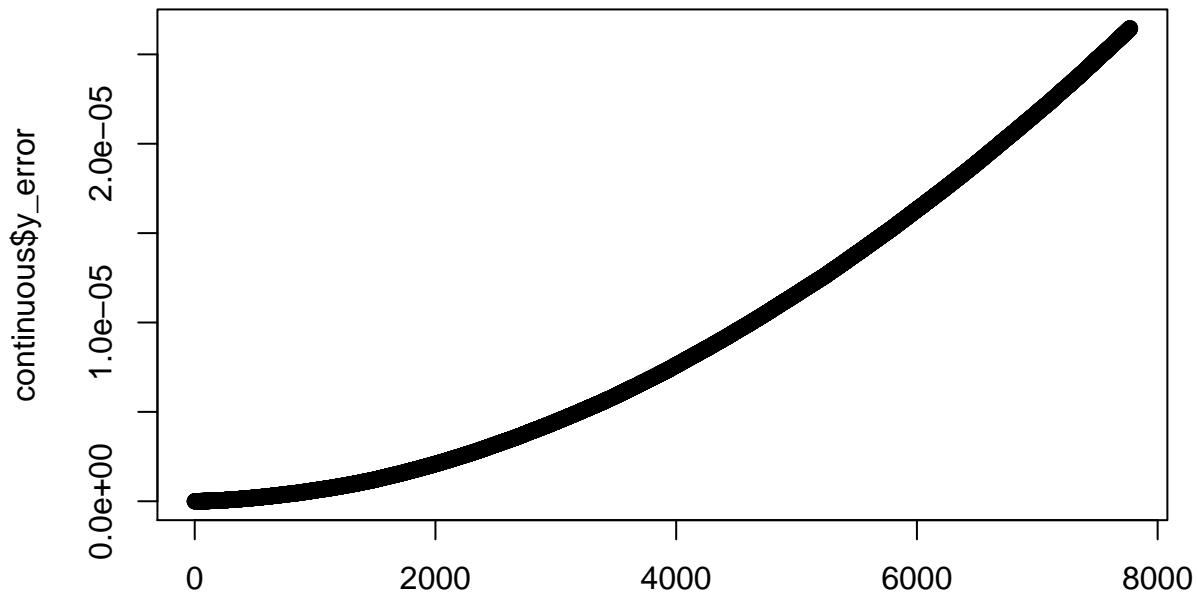
Continuous x_error over time



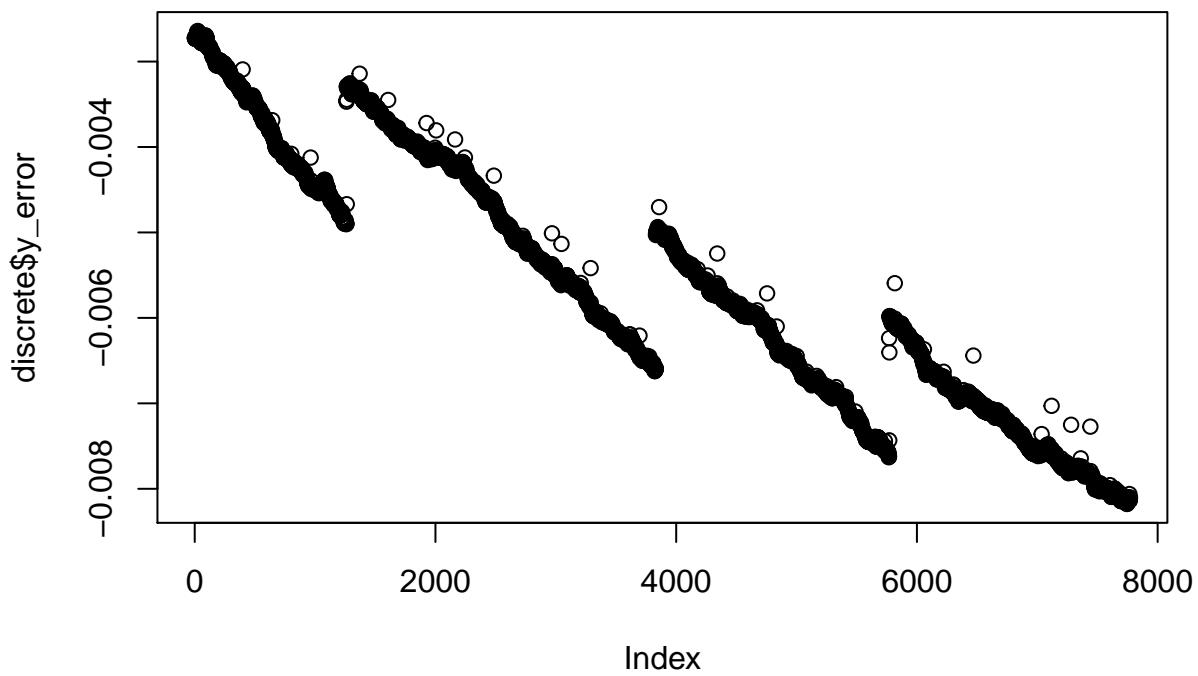
Discrete x_error over time



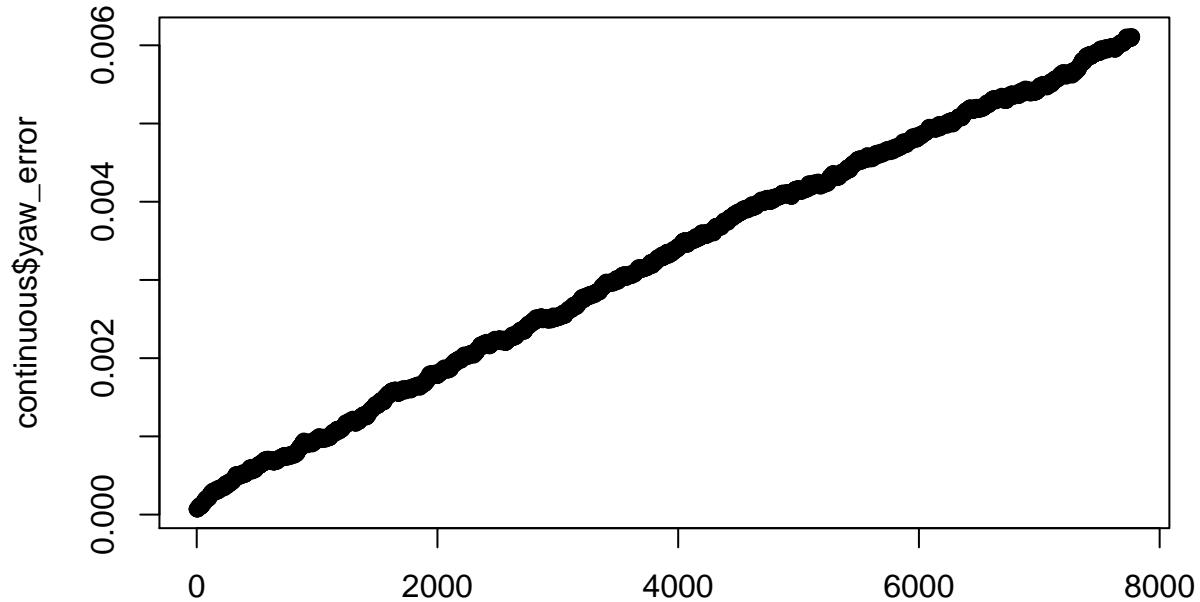
Continuous y_error over time



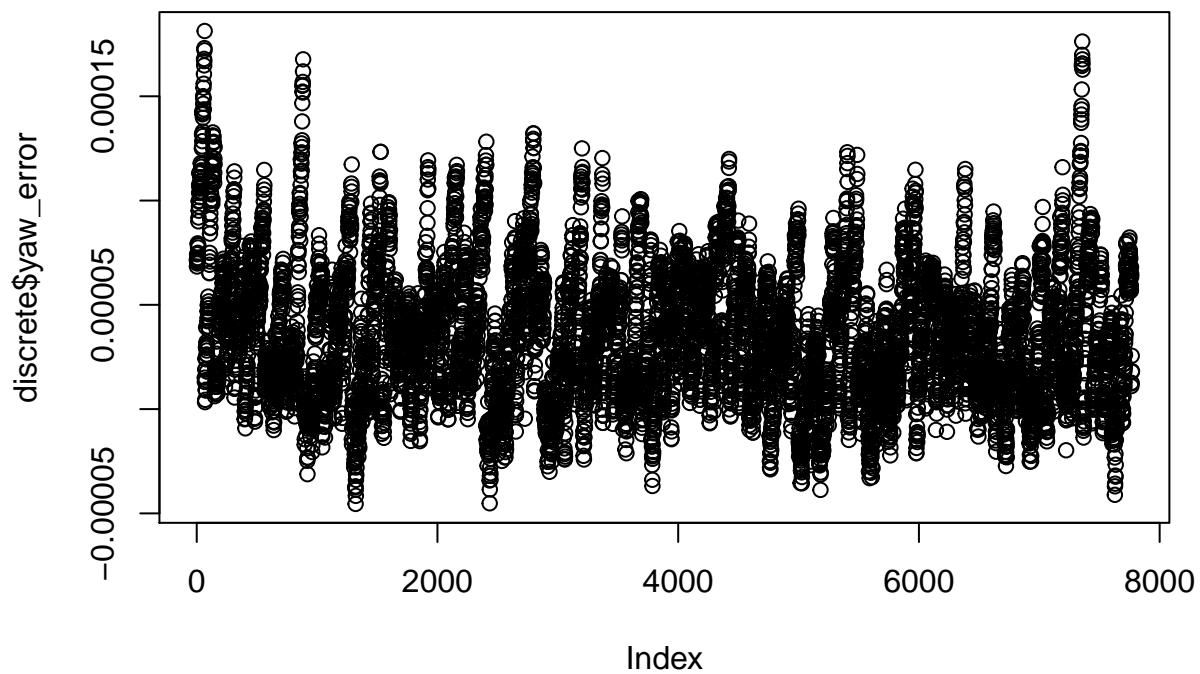
Discrete y_error over time



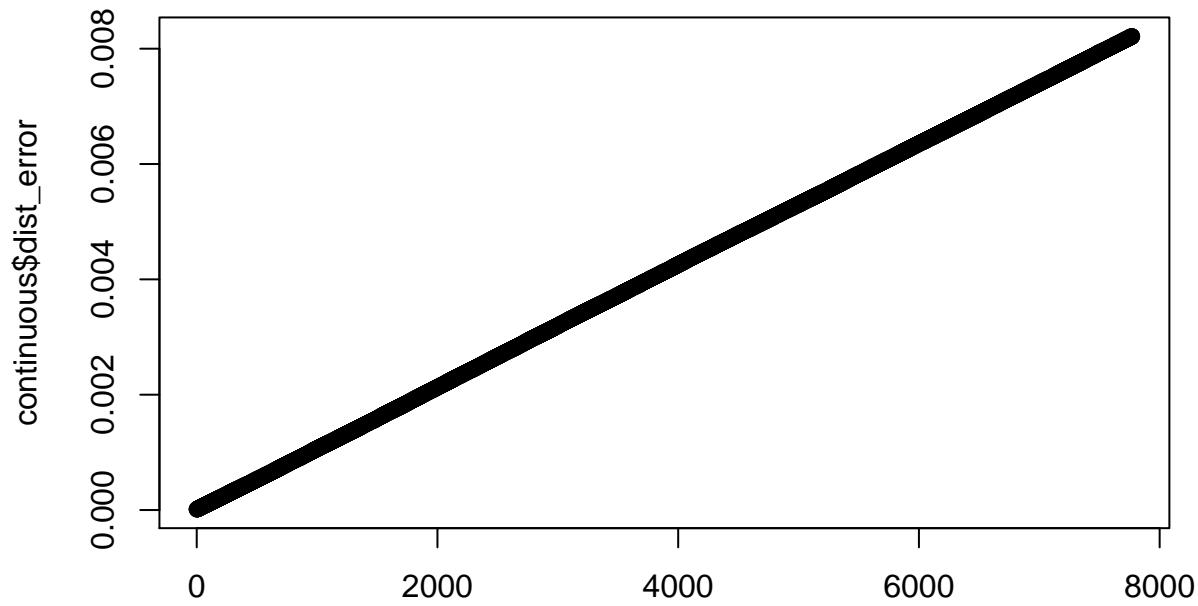
Continuous yaw error over time



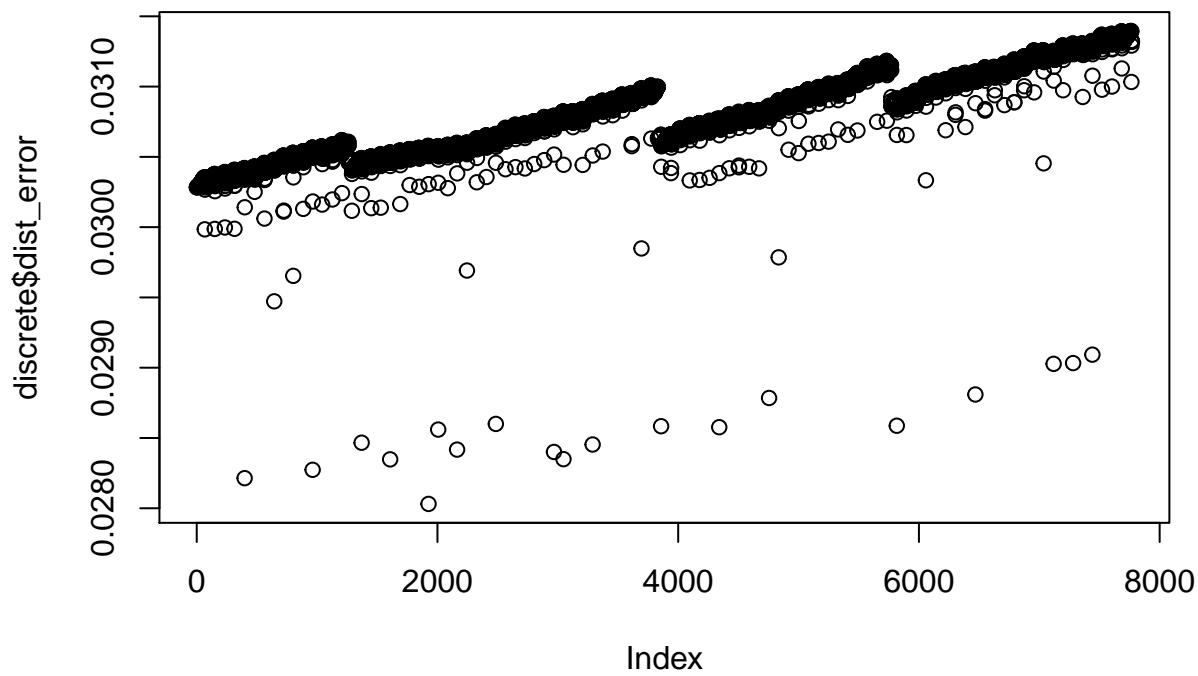
Discrete yaw error over time



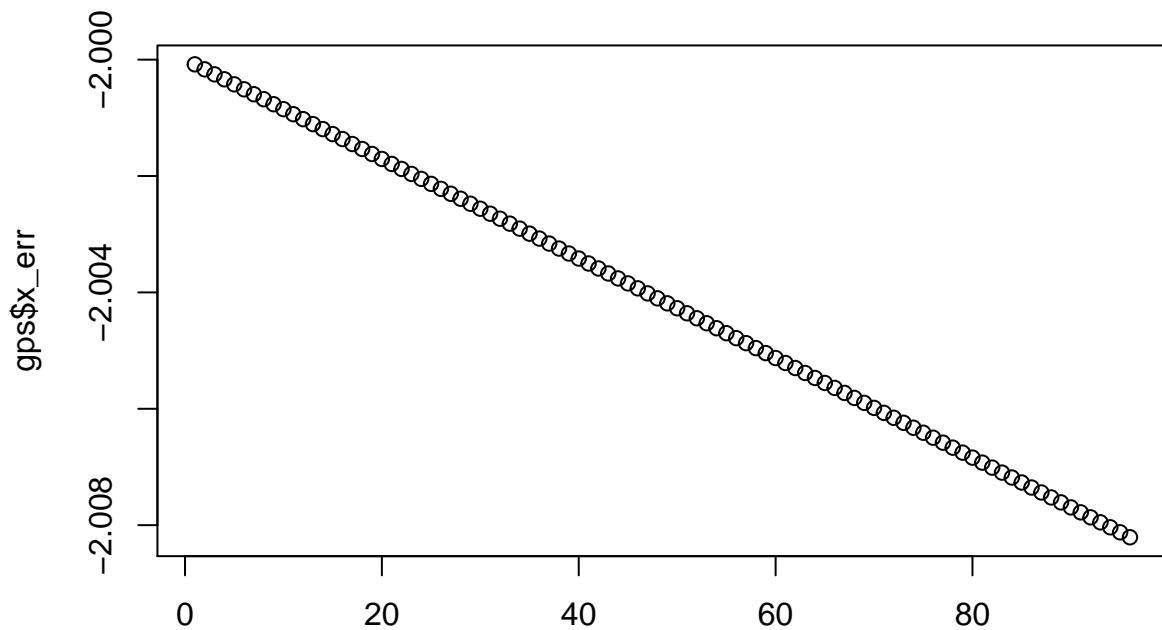
Continuous total distance error over time



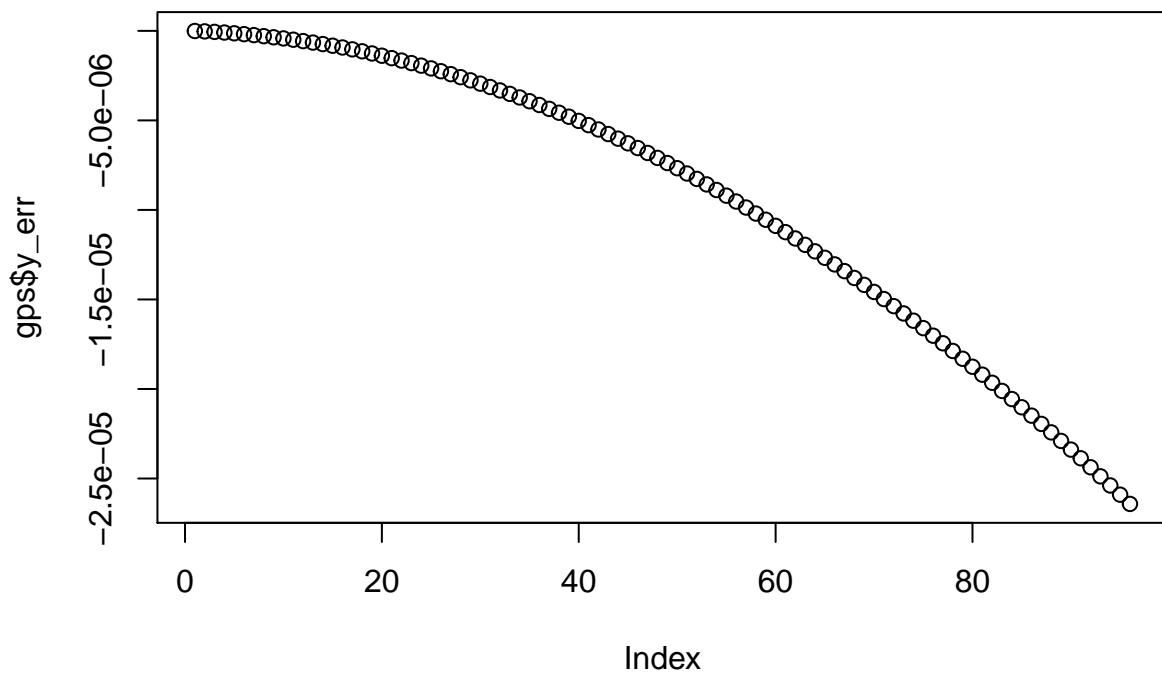
Discrete total distance error over time



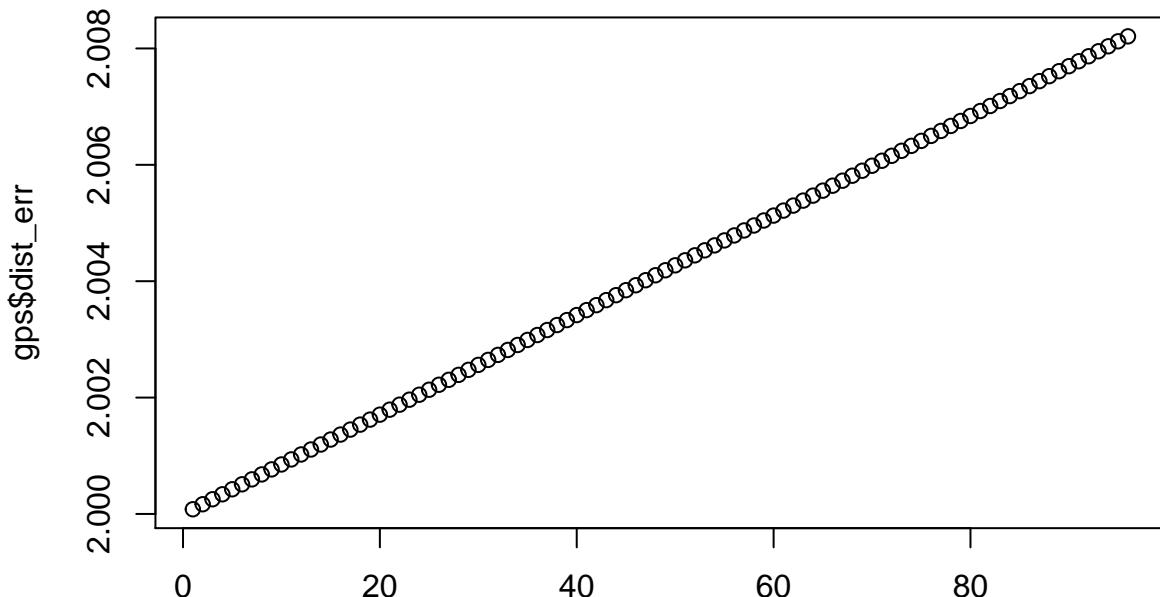
GPS X Error Over Time



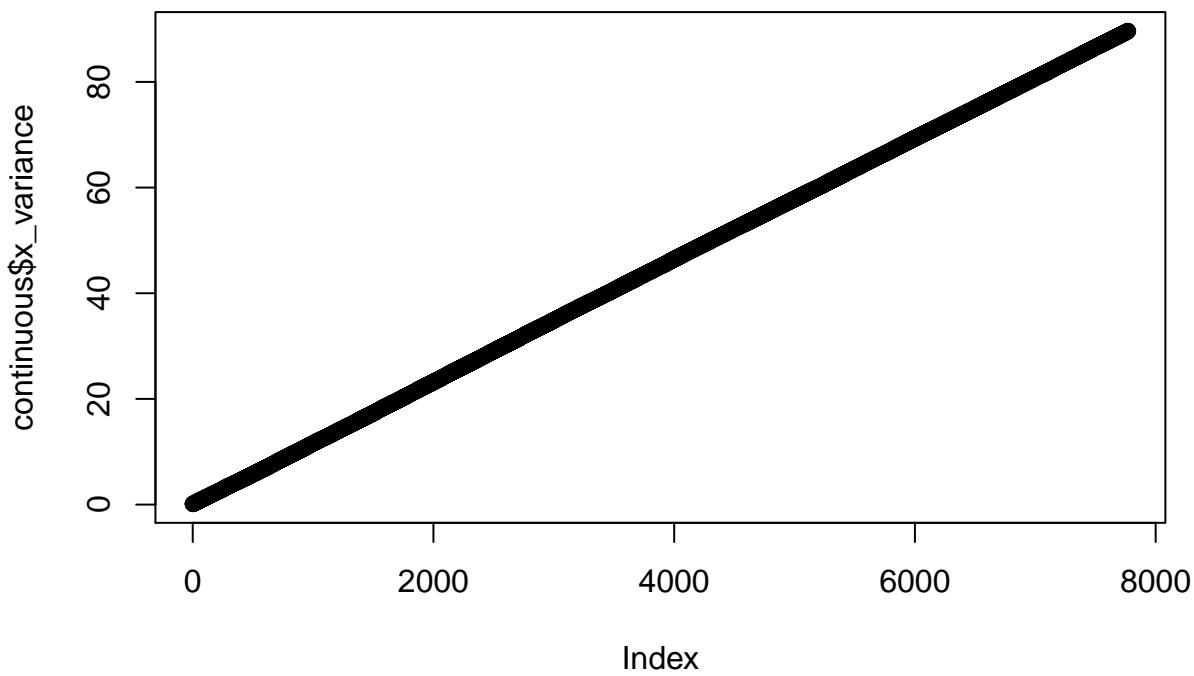
GPS Y Error Over Time



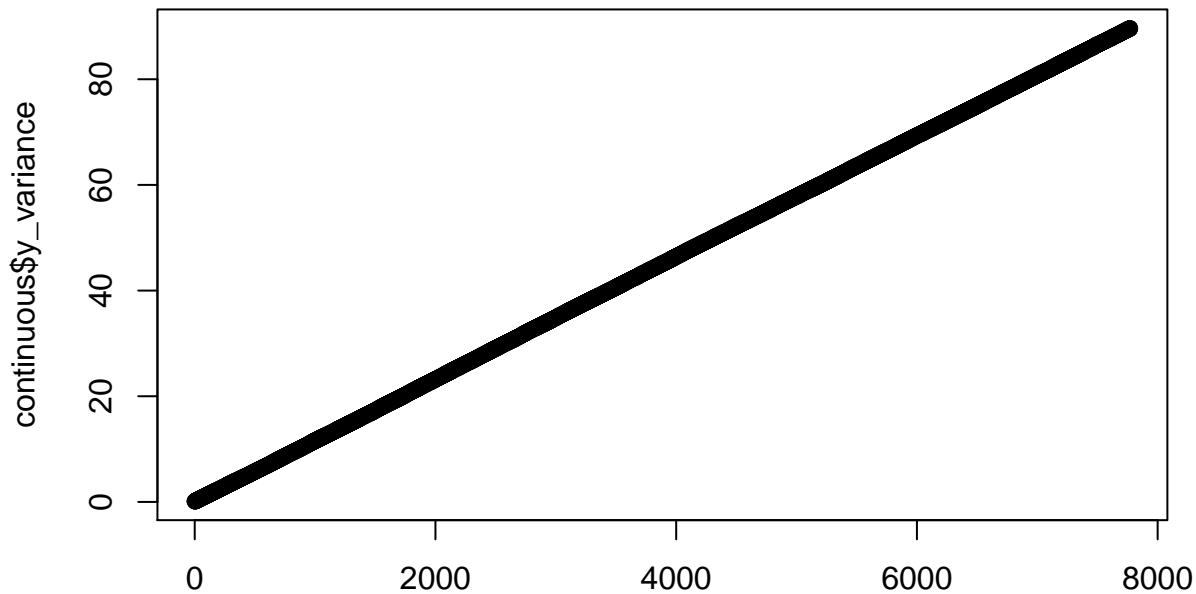
GPS Horizontal Distance Error Over Time



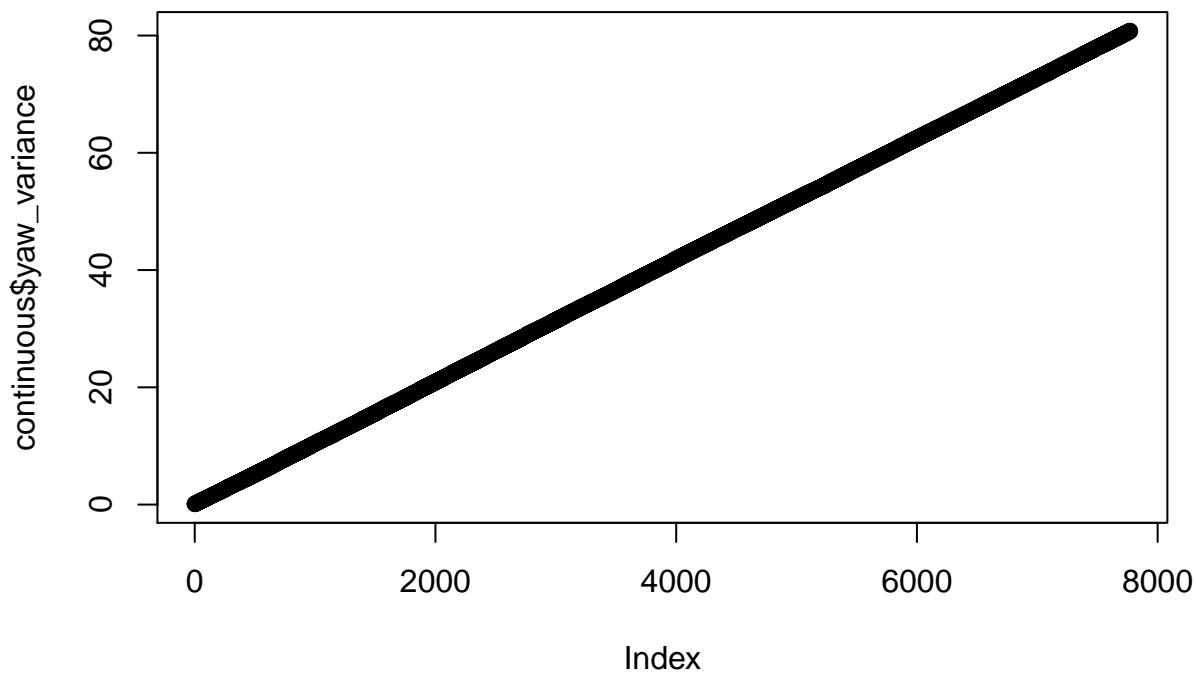
Continuous Filter X Variance Over Time



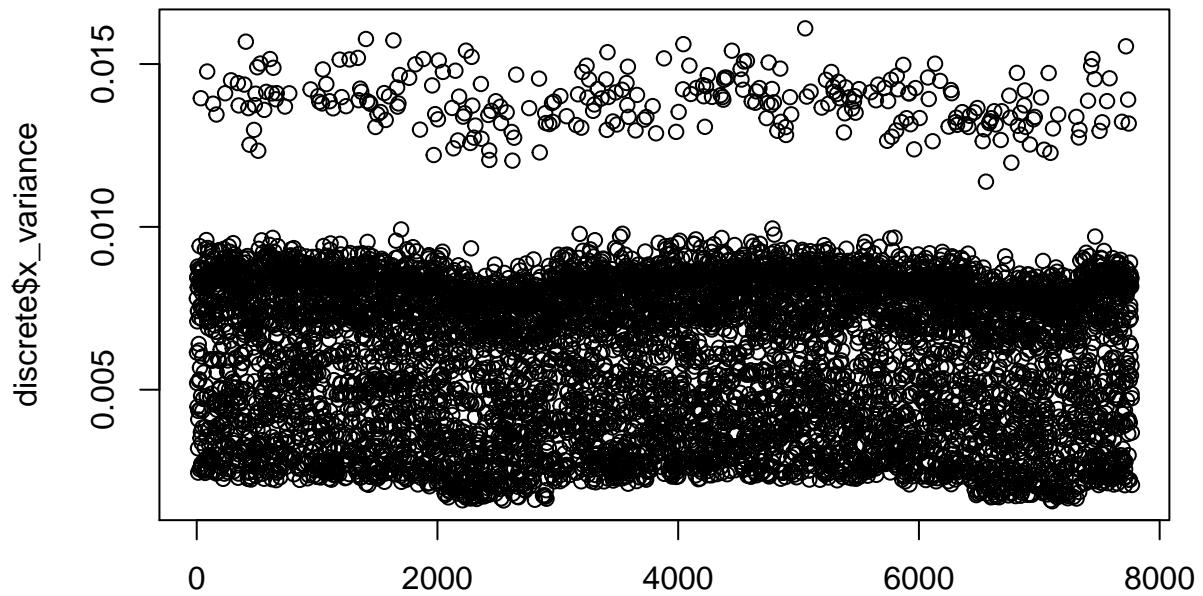
Continuous Filter Y Variance Over Time



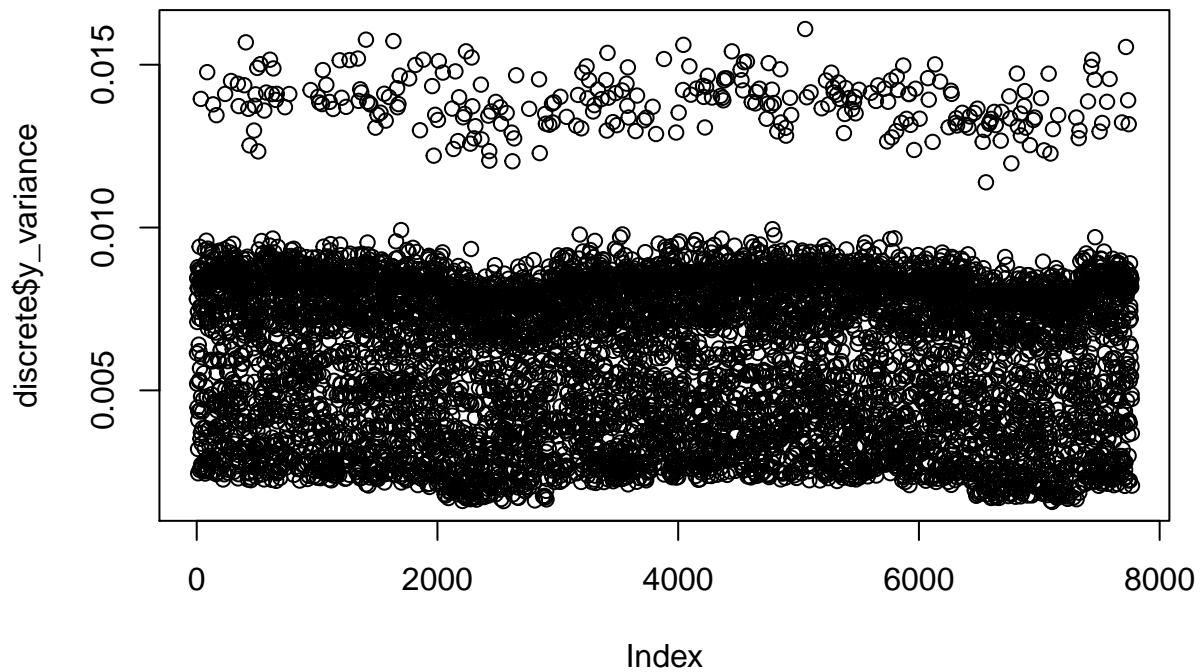
Continuous Filter ^{Index}Yaw Variance Over Time



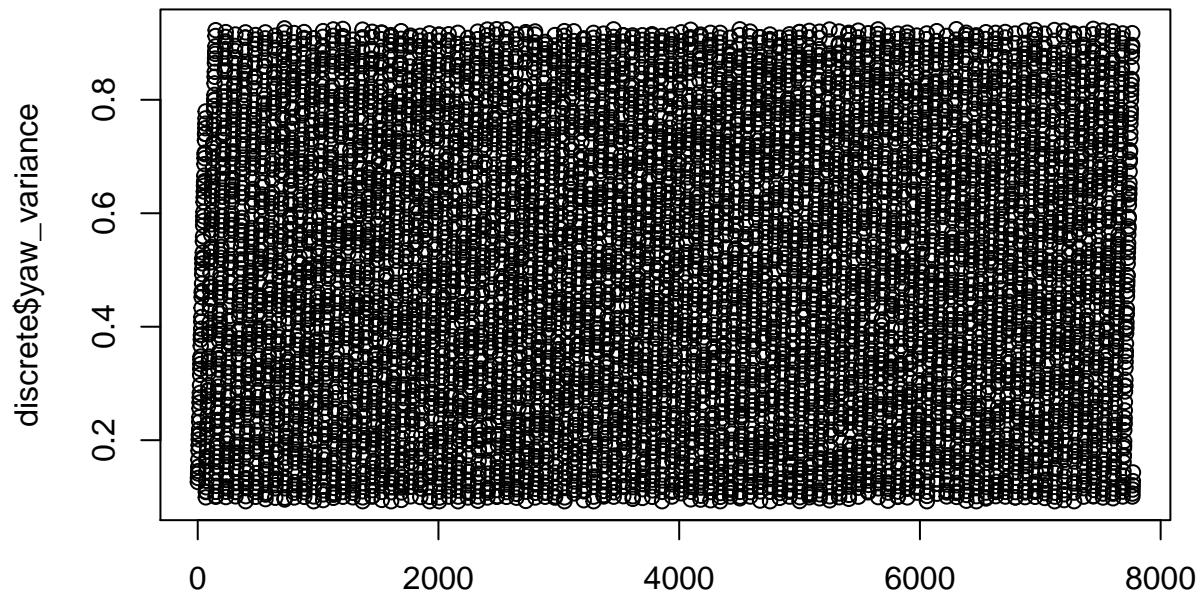
Discrete Filter X Variance Over Time



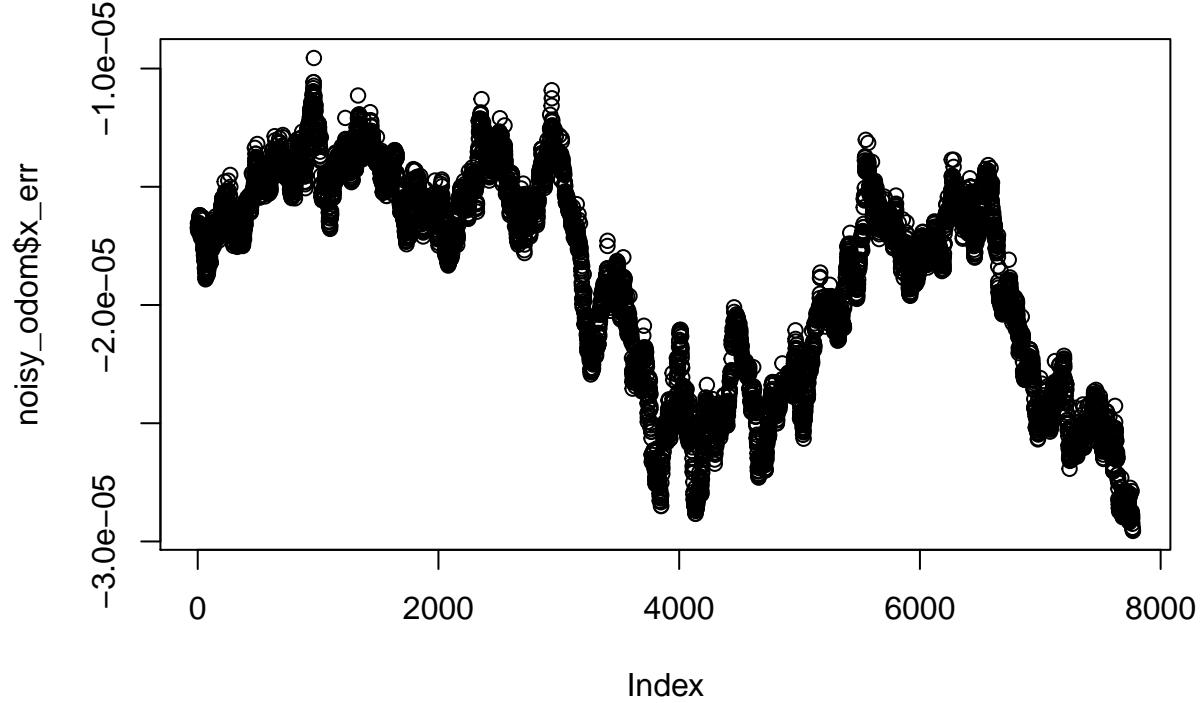
Discrete Filter Y Variance Over Time



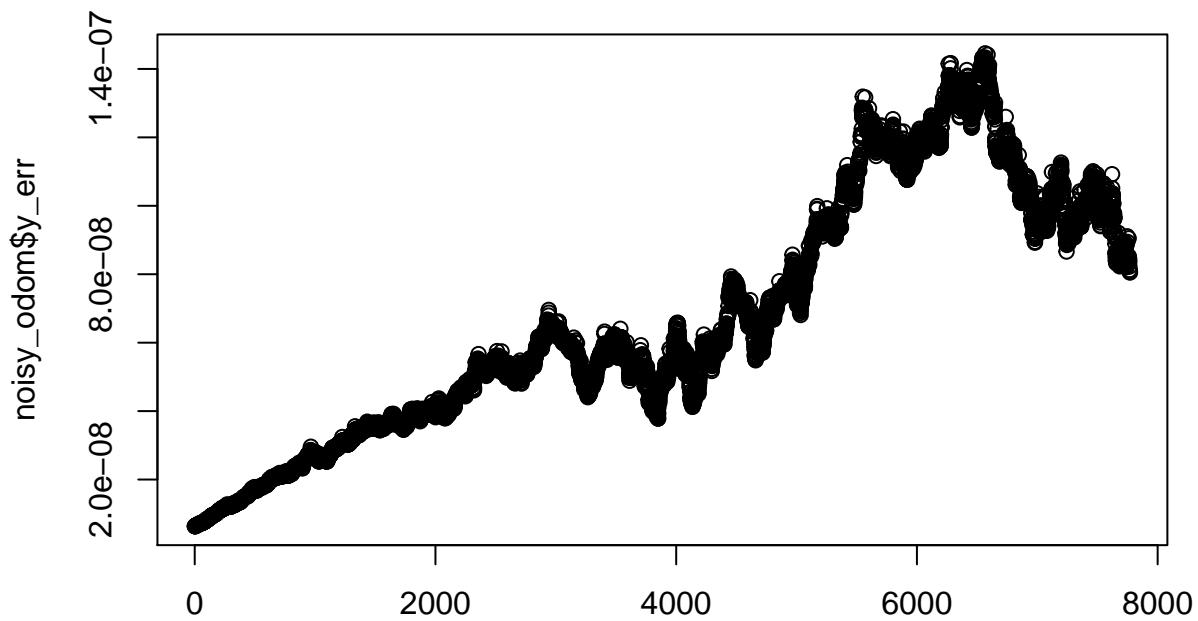
Discrete Filter Yaw Variance Over Time



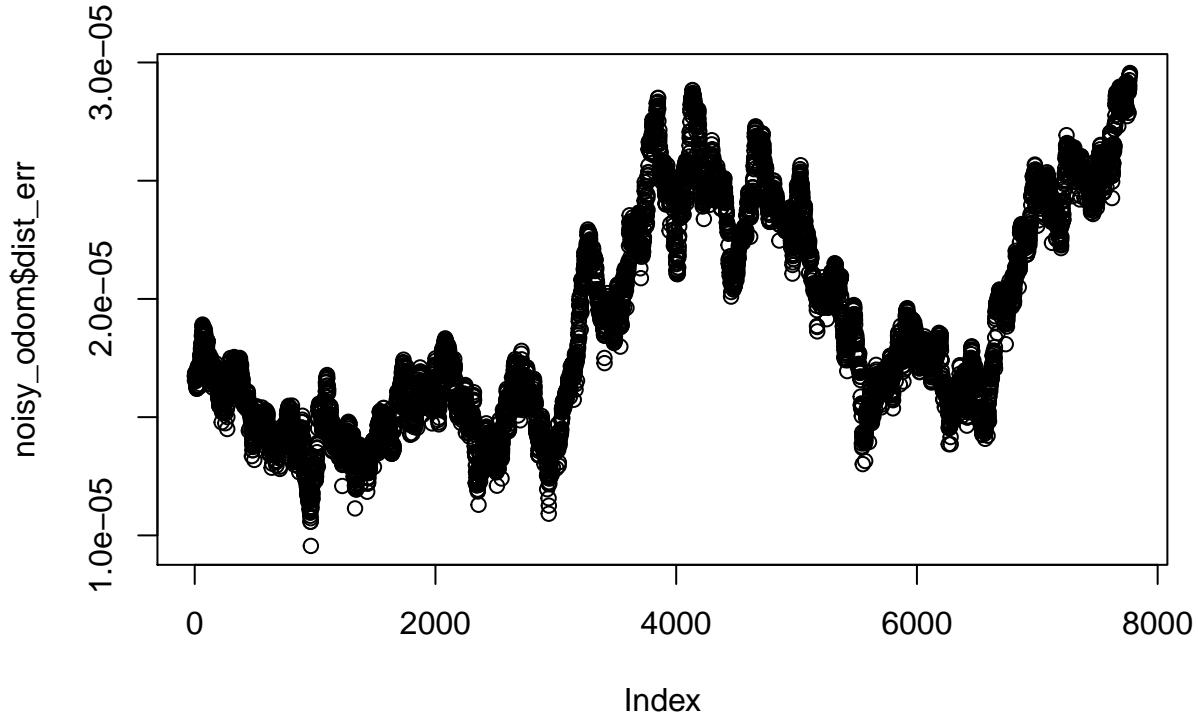
Noisy Odom X Error Over Time^{Index}



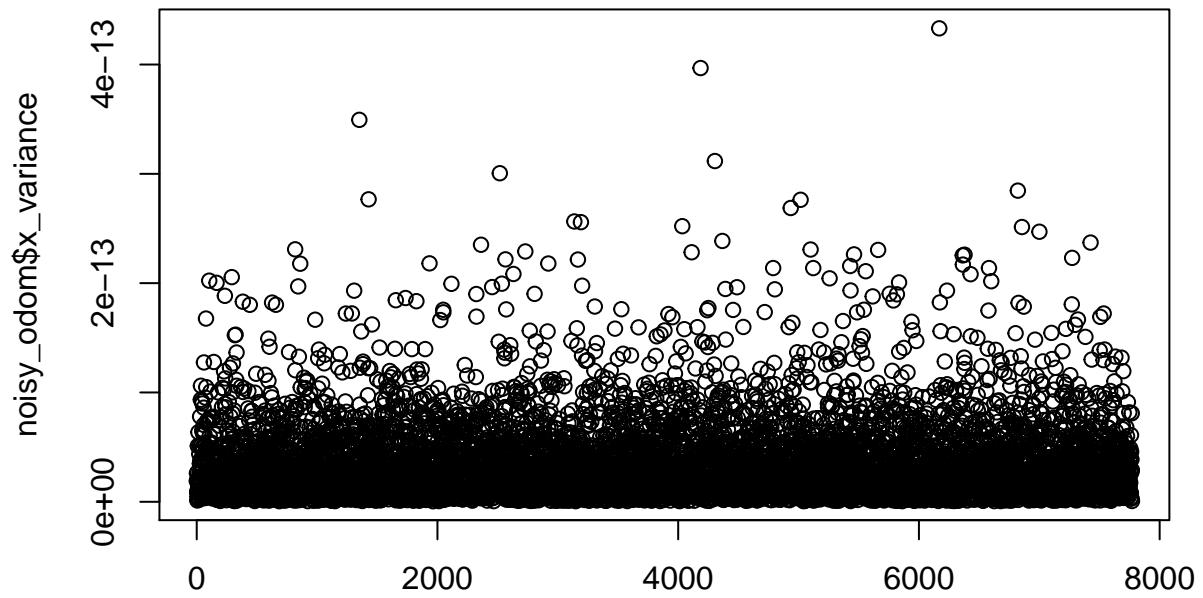
Noisy Odom Y Error Over Time



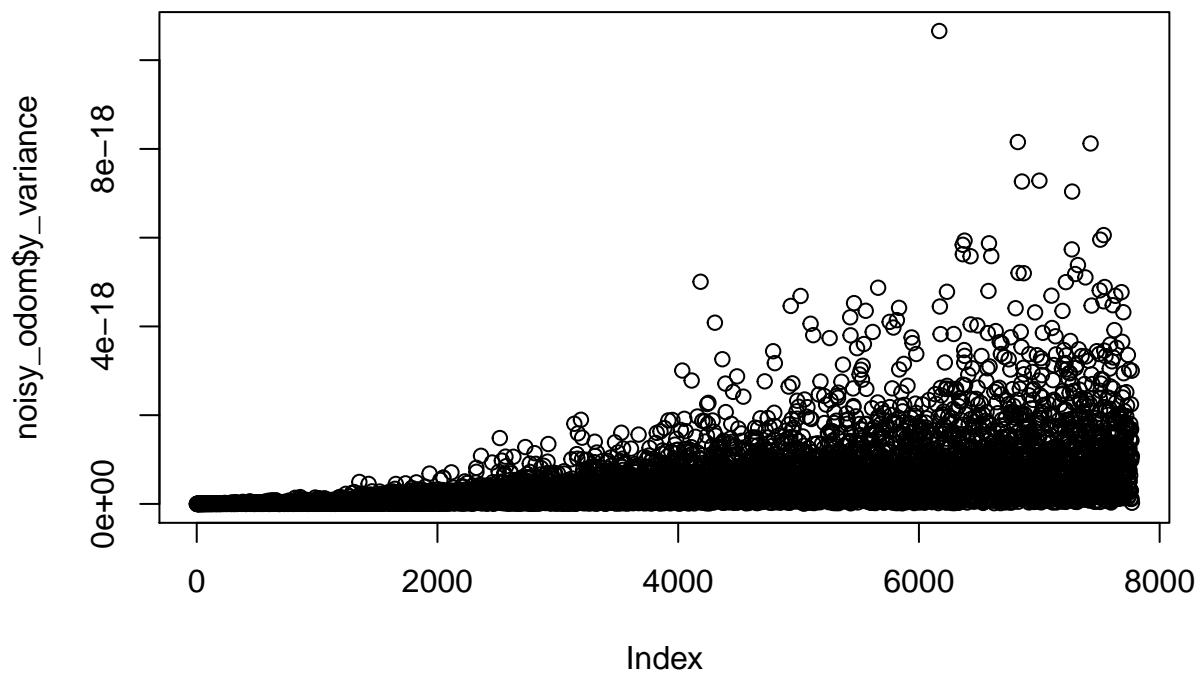
Noisy Odom Horizontal Distance Error Over Time



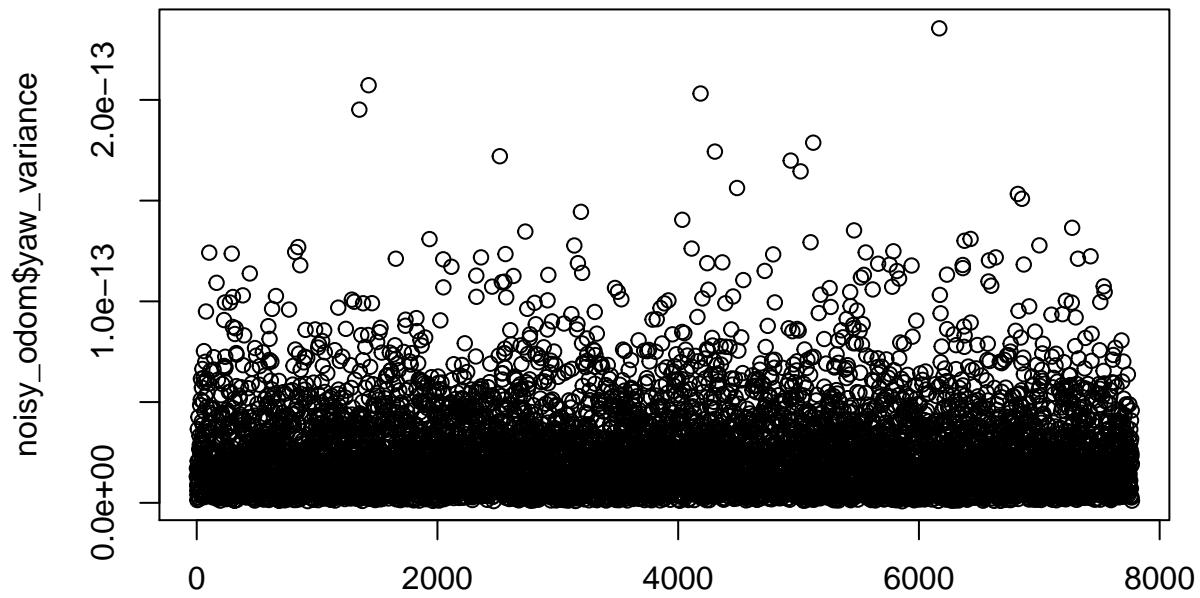
Variance of X Coordinate in Noisy Odometry



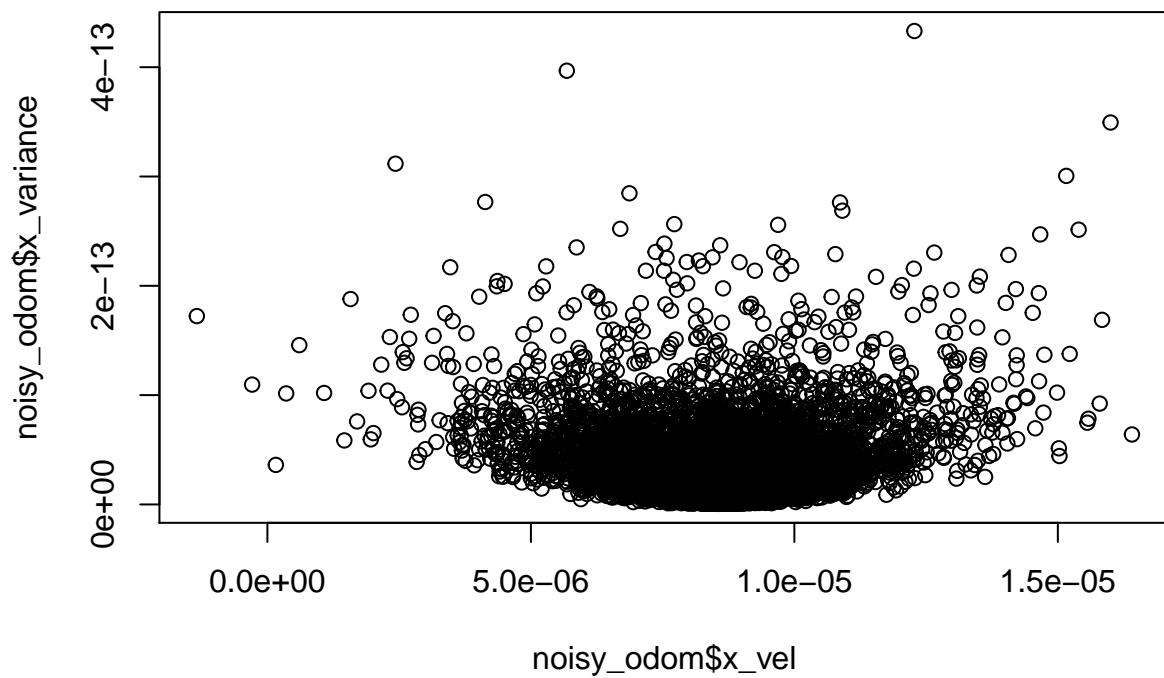
Variance of Y Coordinate in Noisy Odometry



Variance of Yaw Coordinate in Noisy Odometry



Variance vs. Velocity of X in Noisy Odometry



Variance vs. Velocity of Yaw in Noisy Odometry

