main\_7room.py

case.random\_bias\_prob = 0.0

case.py

*self*.init\_p\_wt = 1/float(*self*.num\_particles) if change num\_particles in main, should change this value also.

goalgraph.py

for different maps, we should change the code inside: node\_names, self.start, self.goal\_dirs, self.graph\_nodes and edges

line 131 resample?

Line 136 self.goal\_dirs

Line 137

controller.py

*self*.base = [1, 1]

sensorfly.py

*self*.noise\_fingerprint = [[*self*.noise\_radio/2,0],[0,*self*.noise\_radio/2]]

*self*.sig\_match\_cnt = 0

*self*.last\_goal\_dir = np.zeros([1, 2], dtype=np.float32)

*self*.backoff\_time\_cnt = 0

*self*.sig\_db = case.rf\_signature\_db

robotpf.py

*self*.lm\_covars = np.array([*self*.COVARIANCE\_MATRIX for \_ in range(*self*.num\_particles)])

1. where to get the map and .mat?
2. Different ways to calculate noise:

velocity and turn~N(V,v\*noise), radio & mag~N(d,noise)

1. Planning strategy
2. Drunkwalk Algo