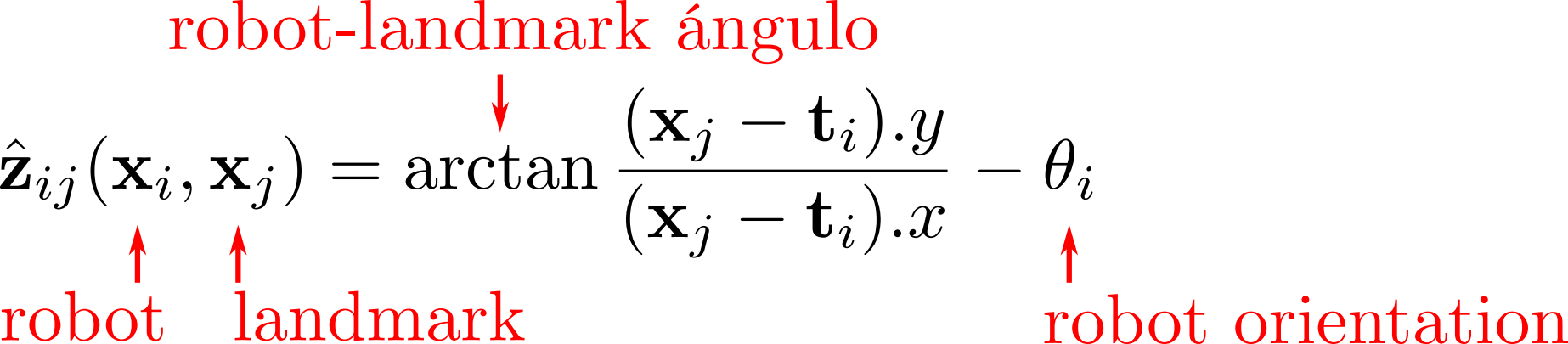
robot-landmark ángulo
$\hat{\mathbf{z}}_{ij}(\mathbf{x}_i, \mathbf{x}_j) = \arctan \frac{(\mathbf{x}_j - \mathbf{t}_i).y}{(\mathbf{x}_j - \mathbf{t}_i).x} - \theta_i$
robot
landmark
robot orientation