**Questions**

After the robot rotates to look at the second pair of markers, the localization particles cluster closer together. There are still some facing the original pair of markers, but most at this point are now pointing toward the second pair. Originally, the robot’s position was facing between the two markers to represent that about half of the particles pointed to each pair. After localizing a second time, however, the robot’s overall position now points toward the second pair of markers. Localizing a third time clusters them even a bit closer, but there are still a few pointing toward the original markers