

Part III

3. The robot's estimate of its x coordinate jumped to about -340. Repeating “loc” made it move up to about -380, and further repetitions moved it closer to about -420 (but never actually -500).
4. The updated pose is quite close to the actual pose (which is slightly unexpected given how far off the last part was).

Part IV

3. The robot was pretty good, within a few centimeters.
4. The robot ended up within 5 degrees of its original heading each time.

Part V

5. The estimated is fairly close to the actual: (-11.49, 54.78) heading 6.14 versus (-11.44, 45.2) heading 6.13. The localization particles have dispersed quite a bit, though. The two farthest particles are (12,8) and (-29, 78).

Part VI

Localization significantly affects the robot's estimates of position, though heading is generally quite close. Estimate changed by as much as (53, -72) after localizing.