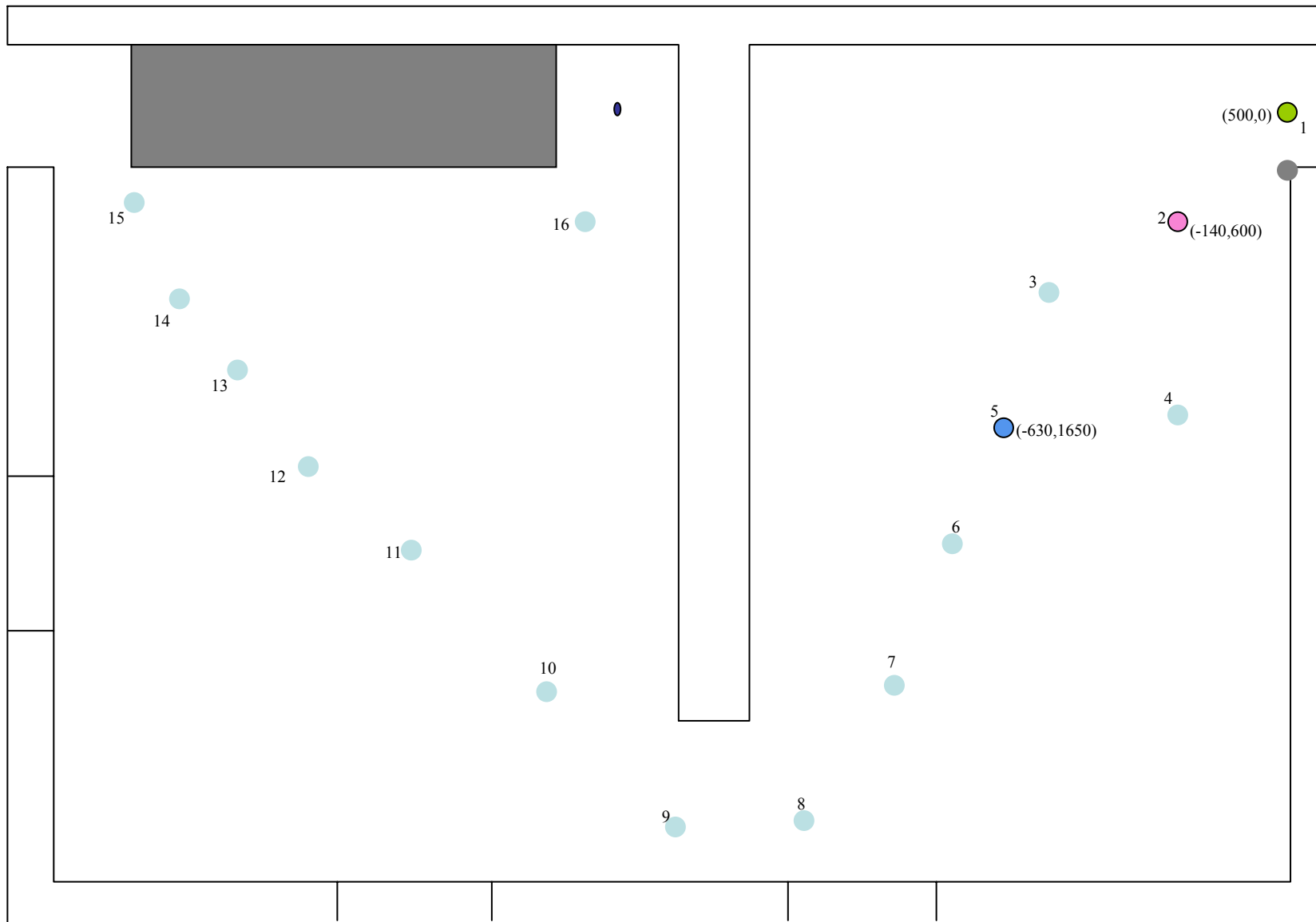
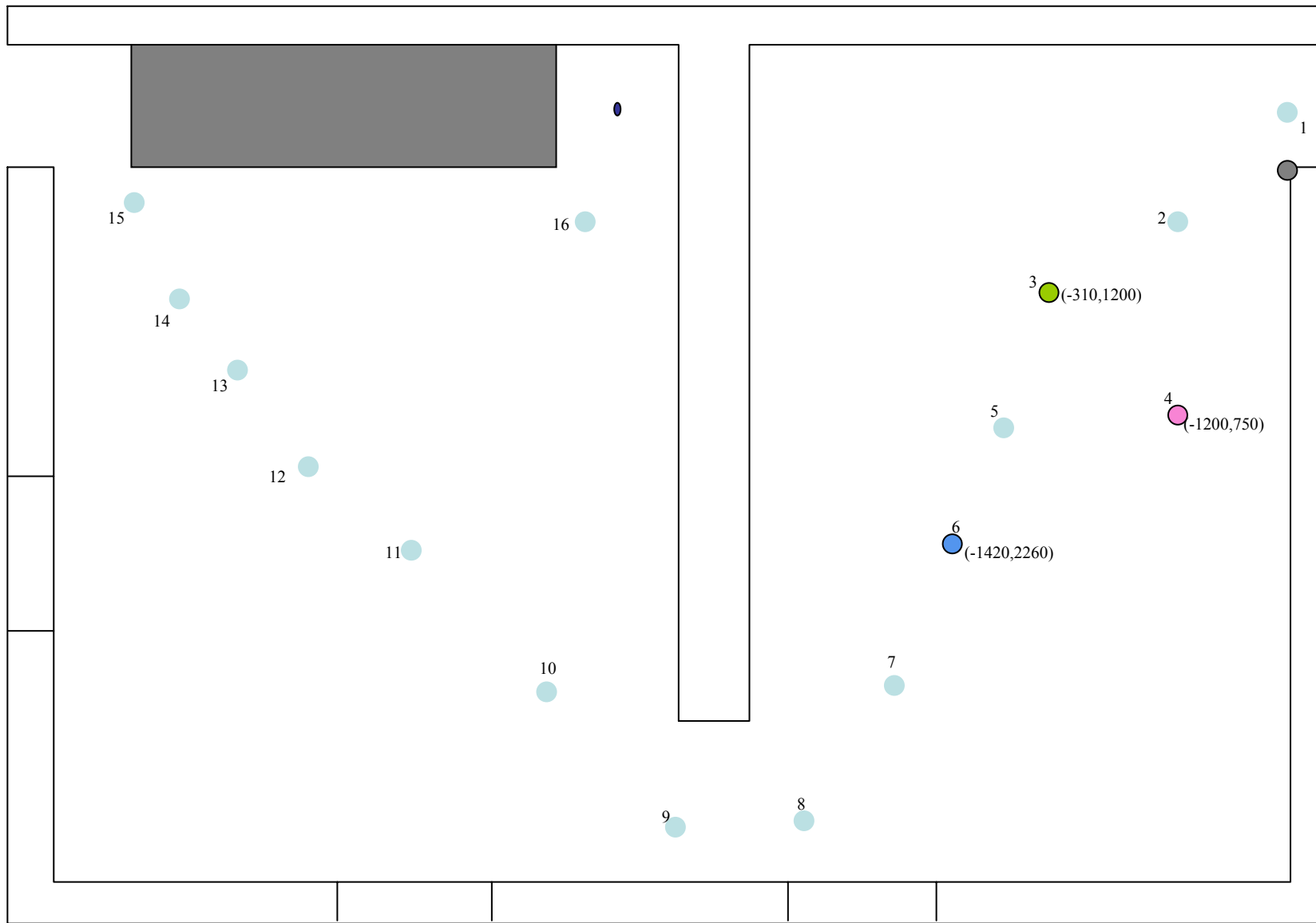


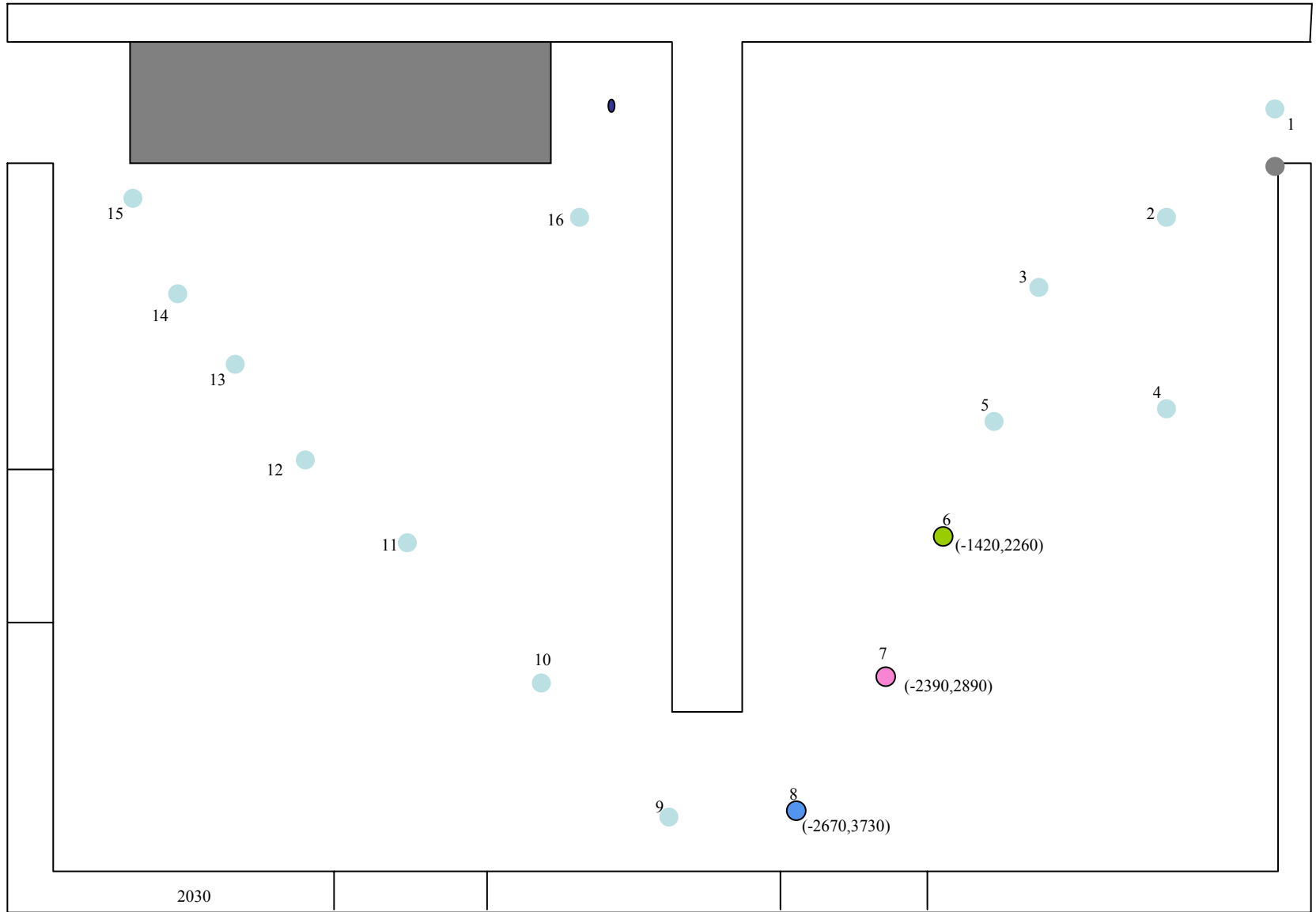
Frame #1



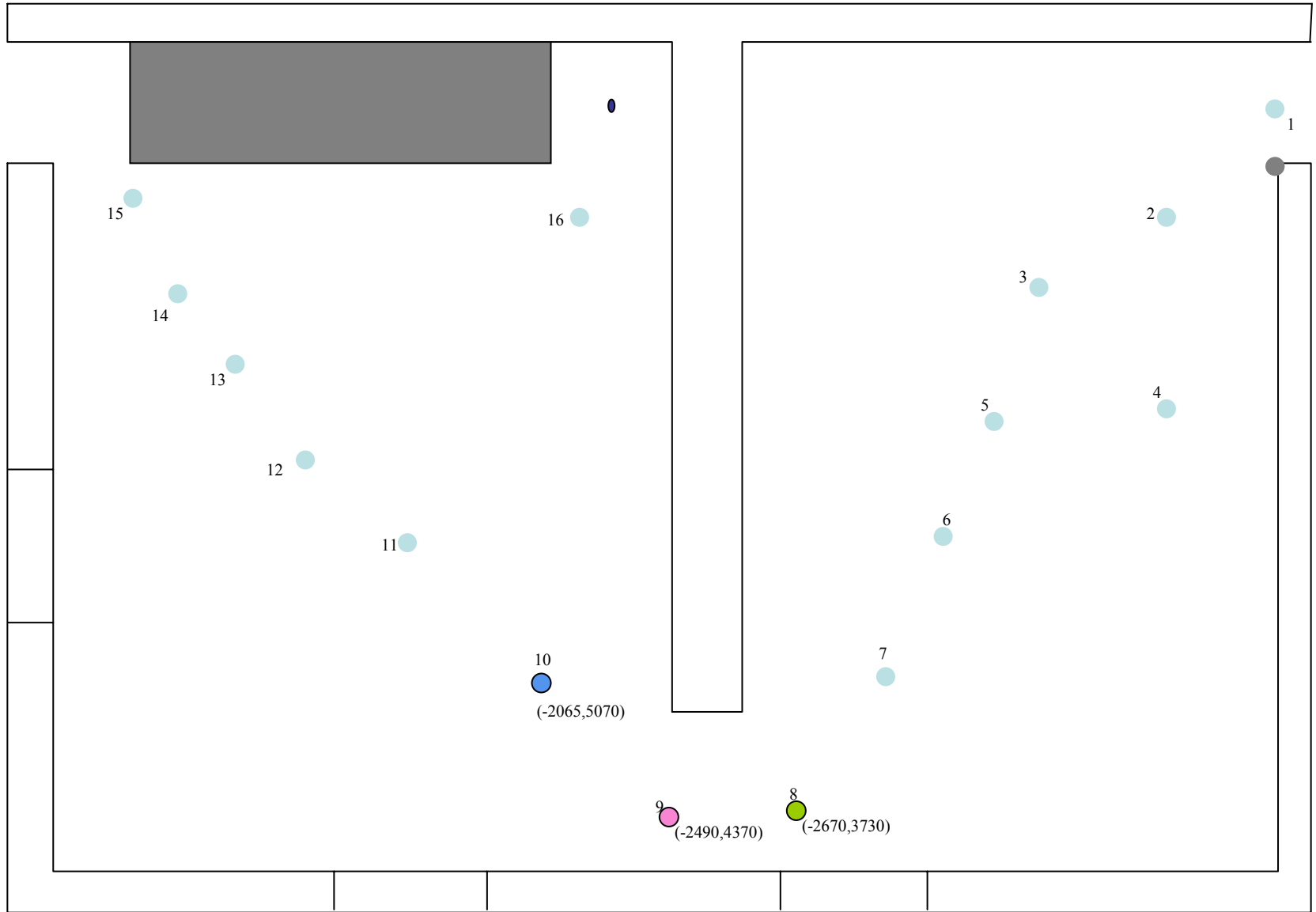
Frame #2



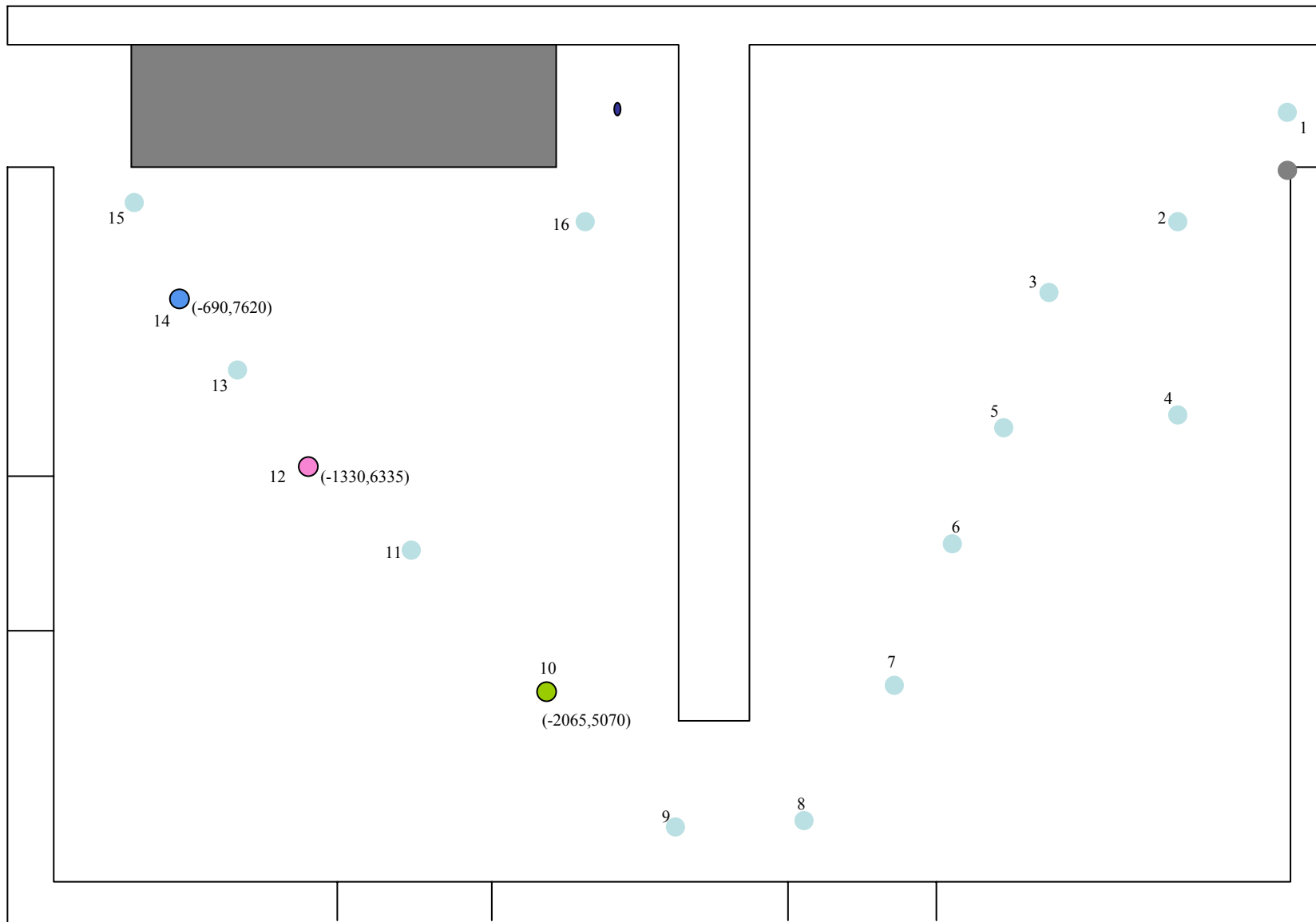
Frame #3



Frame #4



Frame #5



Location of robots in each frame

Frame 1

G:1

B:5

P:2

Frame 2

G:3

B:6

P:4

Frame 3

G:6

B:8

P:7

Frame 4

G:8

B:10

P:9

Frame 5

G:10

B:14

P:12

Estimates

dist(m)			phi(deg)		
12	13	23	12	13	23
0.8498	1.4839	0.8719	12.8507	161.2366	18.0994
0.9656	1.4851	1.4921	36.4714	75.6212	73.0522
1.1420	1.3665	0.6595	16.8253	144.1805	14.0780
0.7316	1.2579	0.9537	8.7506	172.6598	8.5061
1.4807	2.1173	0.9779	4.0142	191.5692	4.6239

Ground Truth

dist(mm)=			phi(deg)=		
12	13	23	12	13	23
877.27	1999.8	1158.7	9.3883	158.17	12.442
997.3	1534.8	1525.9	38.031	71.467	70.502
1156.6	1929.6	885.44	21.941	141.44	16.621
664.83	1470.2	818.92	6.9649	164.44	8.5902
1463	2897.1	1435.6	1.8584	176.32	1.8235