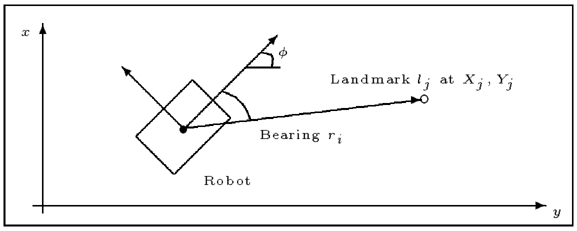
x
ϕ
Landmark l_j at X_j, Y_j
Bearing r_i
Robot
y