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$KvT] = R K E[v KvTj] = 0$  For  $K \neq J$   $E[v KxT0] = 0$  For All  $K$  (4) Also The Two Random  
Vectors  $W K$  And  $V K$  Are Uncorrelated:  $E[w KvT J] = 0$  For All  $K$  And  $J$  (5) Vectorial  
Functions  $F(\cdot)$  And  $H(\cdot)$  Are Assumed To Be  $C1$  Functions (the Function And 1th,  
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The Inertial Measurement Unit (3DM-GX3-25) In Fig. 1 Was Installed Inside Of The  
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Gyroscope At A Sampling Rate Of 100Hz. This Information Is Us 2th, 2024

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The Resulting filter Was Called The Schmidt-Kalman filter (now Called The Extended  
Kalman Filter (EKF), And The Application Was Found For The EKF During The Initial  
Apollo Moon Landings. Recent Work By Julier And Uhlmann [9] Has Produced The  
Unscented Kalman Filter (UKF), Which Can Handle A Much Wider Range Of Non- 1th,  
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In INS/GPS Integrated System, The Accumulating INS Errors Are Effectively Restrained Through Periodical Integration With GPS Observations. Furthermore, The INS Calculation Is At A High Rate, I.e., With A Considerably Small Update Interval Within 0.005 S, Which Shows That The Errors Could Be Small Values. So, In This Work The 3th, 2024

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Sample Matrix Is A Time Average Estimate Of The Array Correlation Matrix Using K-time Samples. If The Random Process Is Ergodic In The Correlation, The Time Average Estimate Will Equal The Actual Correlation Matrix. [3] SMI Weight Vector Can Be Written In The Following Form  $W_{SMI} = \alpha \hat{R}^{-1} a H^T$  1th, 2024

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Introduction The EKF Has Been Applied Extensively To The field Of Non-linear Estimation. General Application areas maybe Divided Into State-estimation And Machine Learning. We Further Di-vide Machine Learning Into Parameter Estimation And Dual Estimation. The Framework For These Areas Are Briefly Re-viewed Next. State-estimation 3th, 2024

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EKF To Pose Estimation In RVS. First, A Known Object Model Is Usually Assumed To Be Available. Model-free Approaches Based On Euclidean Reconstruction Have Been



Proposed For CD Estimation [4], [5]. These Approaches Typically Rely On Fundamental, Essential, And/or Homogra-phy Matrix Estimation, E.g., In [5] And [25] And, Hence, Face The Issue Of 3th, 2024

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