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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, 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, 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  $W_{SMI} = \alpha \hat{R}^{-1} a H \alpha$  1th, 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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