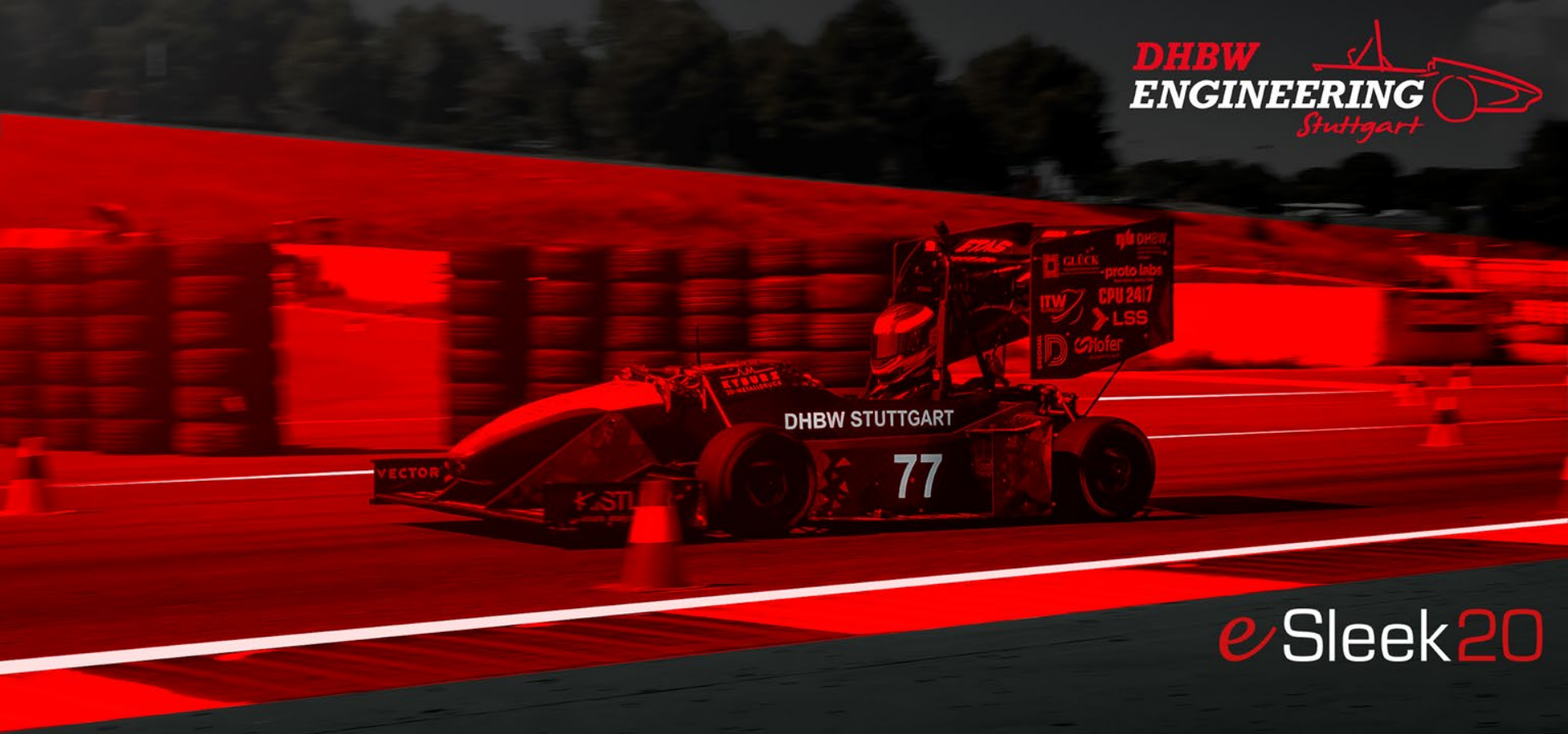



# State Estimation

# Done

- Move VDC to Git
  - Enables offline commits
  - Enables use of Gitlab features (e.g., CI)
  - Separate, clean repo for VDC
- Write unit tests for some functions
  - Just to see how it works, will be used for vehicle model in EKF
- Complete pre-processing block (slightly behind schedule)
  - 3 IMUs not yet supported
- Decide on pose generation with DV

# Next steps

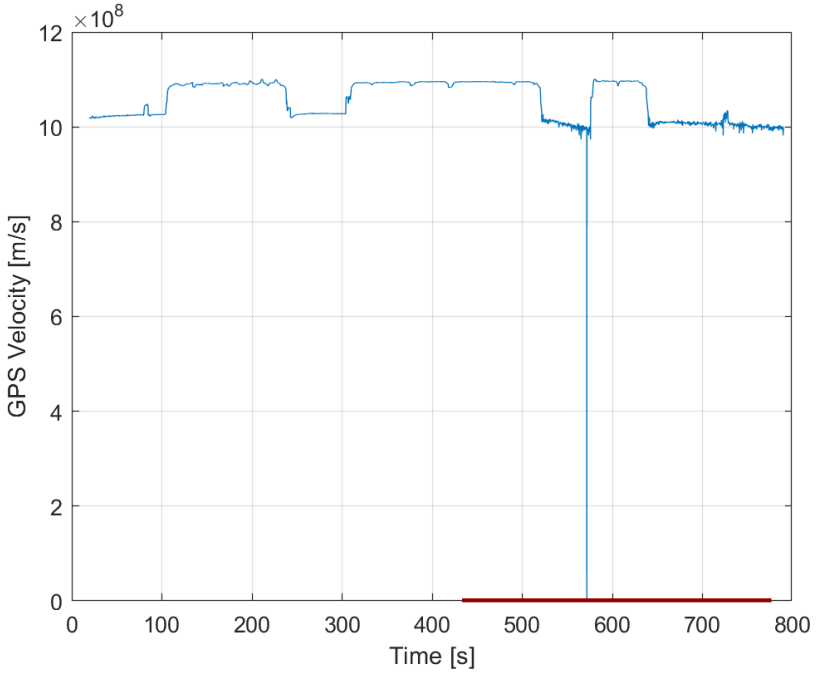
- Create input selector block (measurements and covariances for EKF)
- Create EKF
- Think about detection of available sensors and DV/EV selection
- Integrate DV motion controller into VDC

# INTECRIO Integration

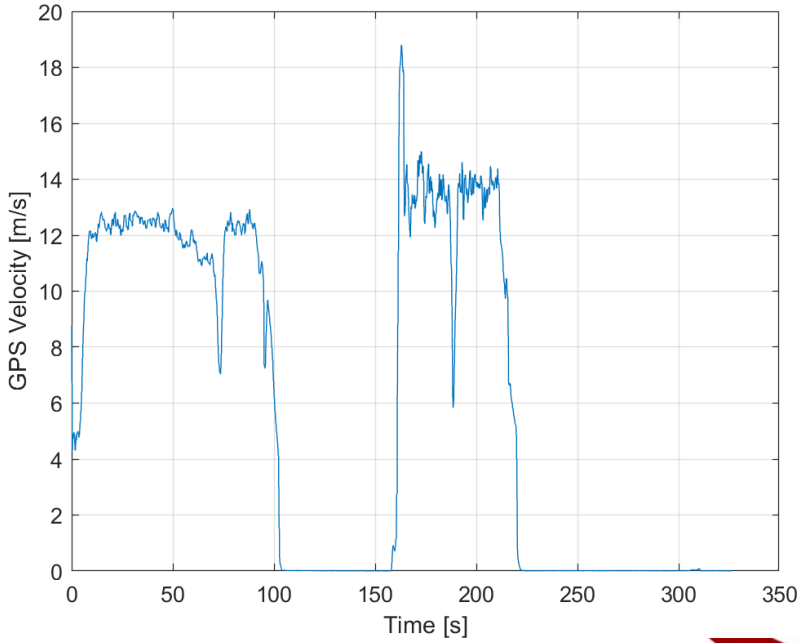
- VDC builds with INTECRIO Real-Time Target with model references
- Necessary modifications:
  - Shared, referenced configuration
  - Data type conversion
  - Unit delay for torque feedback

# GPS Velocity

Datalogger:




ES910:



# Questions

- Warum immer neg. und pos. torque request?
- Wie funktionieren debounce/timeout blocks?
- Wie werden dt-Signale errechnet?
- Wie erkenne ich, ob Sensoren angeschlossen sind?
- Kann man in Intecrio die Parameter sehen?