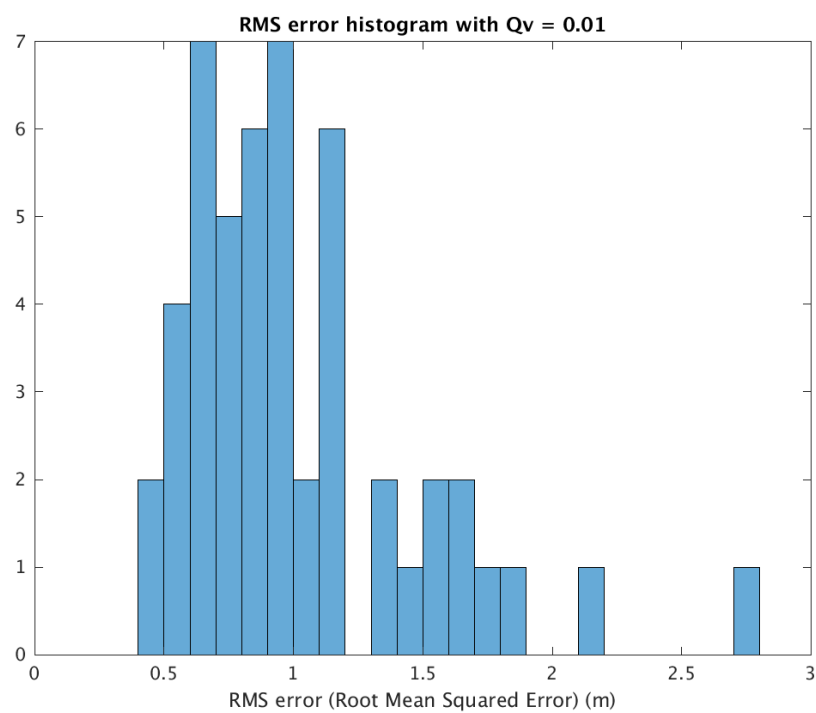

Extended Kalman Filter for Tracking a Three-Wheeled Robot

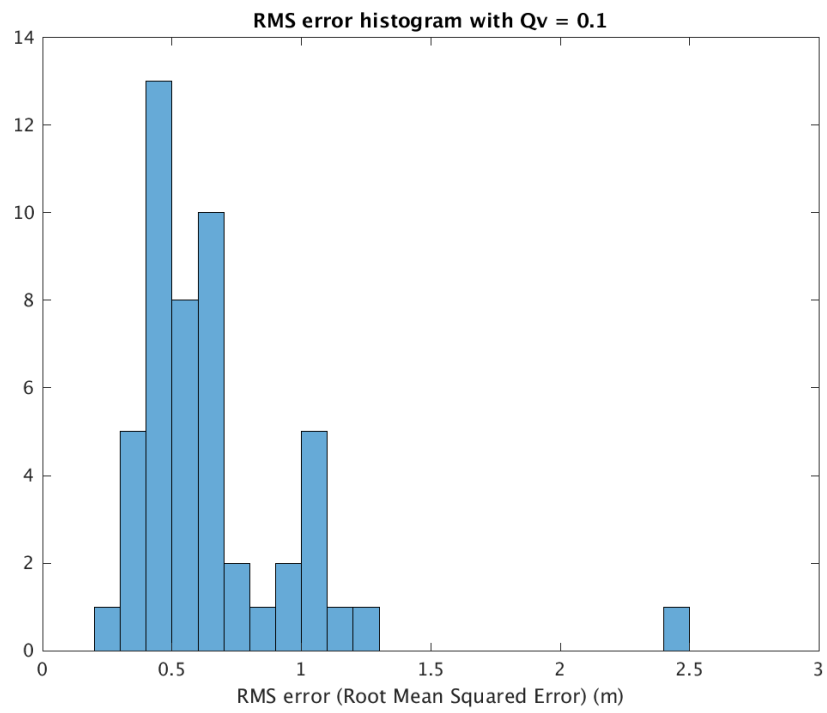
Dong Ho Kang and Jaeyoung Lim

June 7, 2017

- $Q_{v1} = 0.01(\text{rad/s})^2/\text{Hz}$



- $Q_{v2} = 0.1(\text{rad/s})^2/\text{Hz}$



- $Q_{v3} = 1.0(\text{rad/s})^2/\text{Hz}$

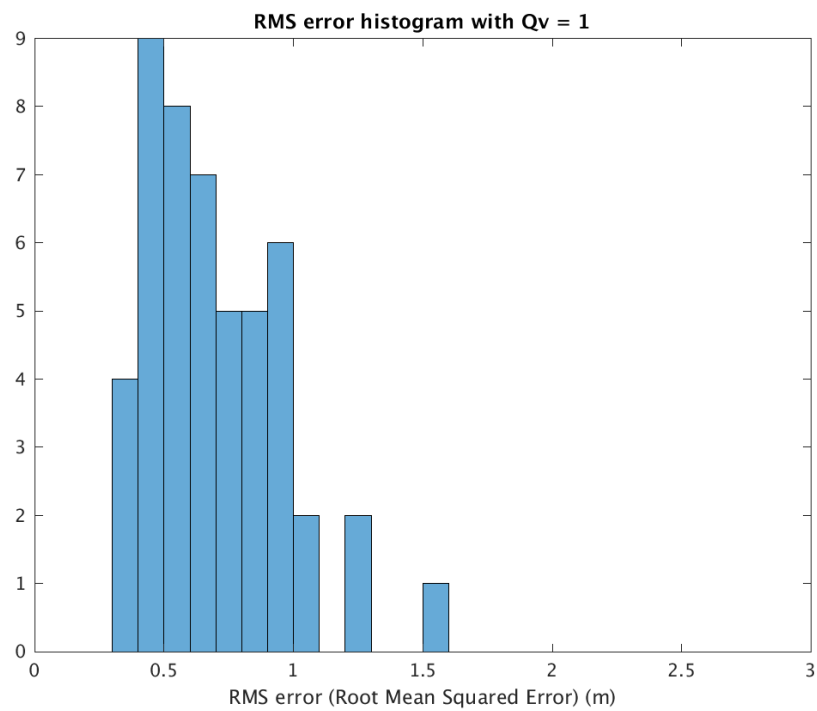
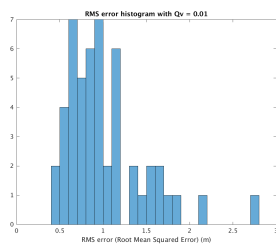
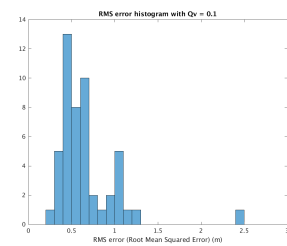


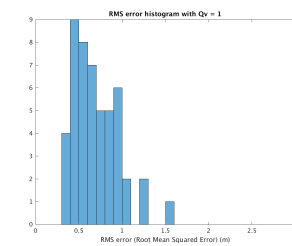
Figure 0.1: batman.jpg



(a) batman.jpg



(b) Scribbles for the color his-



(c) Scribbles for the color his-