This document defines the formulas required for a Kalman filter that is used to localize the EduArt robots globally.

1 Prediction Model for Eduard with Mecanum

1.1 Acceleration

$$\mathbf{a}_{t-1} = \begin{pmatrix} a_{x_{t-1}} \\ a_{y_{t-1}} \end{pmatrix} \tag{1}$$

$$\mathbf{a}_{t} = \begin{pmatrix} a_{x_{t-1}} \\ a_{y_{t-1}} \end{pmatrix} \tag{2}$$

1.2 Velocity

$$\mathbf{v}_{t-1} = \begin{pmatrix} v_{x_{t-1}} \\ v_{y_{t-1}} \end{pmatrix} \tag{3}$$

$$\mathbf{v}_{t} = \begin{pmatrix} a_{x_{t-1}} dt + v_{x_{t-1}} \\ a_{y_{t-1}} dt + v_{y_{t-1}} \end{pmatrix} \tag{4}$$

1.3 Yaw

$$\phi_{z_t} = \phi_{z_{t-1}} + \frac{d}{dt}\phi_{z_{t-1}} dt \tag{5}$$

$$\frac{d}{dt}\phi_{z_t} = \frac{d}{dt}\phi_{z_{t-1}} \tag{6}$$

1.4 Position

$$\cos_\phi = \cos\left(\phi_{z_{t-1}}\right) \tag{7}$$

$$\sin_\phi = \sin\left(\phi_{z_{t-1}}\right) \tag{8}$$

$$\mathbf{R}_{t-1} = \begin{pmatrix} \cos_\phi & -\sin_\phi \\ \sin_\phi & \cos_\phi \end{pmatrix} \tag{9}$$

$$\mathbf{p}_{t-1} = \begin{pmatrix} p_{x(t-1)} \\ p_{y(t-1)} \end{pmatrix} \tag{10}$$

$$\mathbf{p}_{t} = \mathbf{p}_{t-1} + \mathbf{R}_{t-1}\mathbf{v}_{t-1} dt + \frac{1}{2}\mathbf{R}_{t-1}\mathbf{a}_{t-1} dt^2 \tag{11}$$

$$= \begin{pmatrix} dt^2 \left(0.5 a_{x_{t-1}} \cos_\phi - 0.5 a_{y_{t-1}} \sin_\phi\right) + dt\left(v_{x_{t-1}} \cos_\phi - v_{y_{t-1}} \sin_\phi\right) + p_{x(t-1)} \\ dt^2 \left(0.5 a_{x_{t-1}} \sin_\phi + 0.5 a_{y_{t-1}} \cos_\phi\right) + dt\left(v_{x_{t-1}} \sin_\phi + v_{y_{t-1}} \cos_\phi\right) + p_{y(t-1)} \end{pmatrix} \tag{12}$$

1.5 Model

$$\mathbf{F}_t = \begin{pmatrix} p_{x_t} \\ p_{y_t} \\ v_{x_t} \\ v_{y_t} \\ a_{x_t} \\ a_{y_t} \\ \phi_t \\ \dot{\phi}_t \end{pmatrix} = \begin{pmatrix} dt^2\left(0.5a_{x_{t-1}}\cos_\phi - 0.5a_{y_{t-1}}\sin_\phi\right) + dt\left(v_{x_{t-1}}\cos_\phi - v_{y_{t-1}}\sin_\phi\right) + p_{x(t-1)} \\ dt^2\left(0.5a_{x_{t-1}}\sin_\phi + 0.5a_{y_{t-1}}\cos_\phi\right) + dt\left(v_{x_{t-1}}\sin_\phi + v_{y_{t-1}}\cos_\phi\right) + p_{y(t-1)} \\ a_{x_{t-1}}dt + v_{x_{t-1}} \\ a_{y_{t-1}}dt + v_{y_{t-1}} \\ a_{x_{t-1}} \\ a_{y_{t-1}} \\ \dot{\phi}_{z_{t-1}}dt + \phi_{z_{t-1}} \\ \dot{\phi}_{z_{t-1}} \end{pmatrix} \tag{13}$$

$$\mathbf{J}_t = \mathbf{F}\begin{pmatrix} \frac{\partial}{\partial p_x} & \frac{\partial}{\partial p_y} & \frac{\partial}{\partial v_x} & \frac{\partial}{\partial v_y} & \frac{\partial}{\partial a_x} & \frac{\partial}{\partial a_y} & 0 & \frac{\partial}{\partial \phi} \end{pmatrix} \tag{14}$$

$$= \begin{pmatrix} 1 & 0 & dt\cos_\phi & -dt\sin_\phi & 0.5dt^2\cos_\phi & -0.5dt^2\sin_\phi & 0 & 0 \\ 0 & 1 & dt\sin_\phi & dt\cos_\phi & 0.5dt^2\sin_\phi & 0.5dt^2\cos_\phi & 0 & 0 \\ 0 & 0 & 1 & 0 & dt & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 & 0 & dt & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 1 & dt \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 1 \end{pmatrix} \tag{15}$$

2 System Noise Model

2.1 Via Acceleration

The system noise is partly determined by the acceleration that the robot can experience.

$$a = a_x = a_y \tag{16}$$

$$\mathbf{a} = \begin{pmatrix} a \\ a \end{pmatrix} \tag{17}$$

$$\mathbf{v} = \begin{pmatrix} a \cdot dt \\ a \cdot dt \end{pmatrix} \tag{18}$$

$$\mathbf{p} = \frac{1}{2}\mathbf{R}_{t-1}\mathbf{a} \cdot dt^2 \tag{19}$$

$$= \begin{pmatrix} dt^2\left(-0.5 \cdot a \cdot \sin_\phi + 0.5 \cdot a \cdot \cos_\phi\right) \\ dt^2\left(0.5 \cdot a \cdot \sin_\phi + 0.5 \cdot a \cdot \cos_\phi\right) \end{pmatrix} \tag{20}$$

$$\mathbf{a}_{\text{noise}} = \begin{pmatrix} \mathbf{p} \\ \mathbf{v} \\ \mathbf{a} \\ 0 \\ 0 \end{pmatrix} = \begin{pmatrix} 0.5\sqrt{2}dt^2\cos\left(\phi_{z_{t-1}} + \frac{\pi}{4}\right) \\ 0.5\sqrt{2}dt^2\sin\left(\phi_{z_{t-1}} + \frac{\pi}{4}\right) \\ dt \\ dt \\ 1 \\ 1 \\ 0 \\ 0 \end{pmatrix} a \tag{21}$$

$$\mathbf{Q}_{\mathbf{a}} = \sigma_{\mathbf{a}}^2 \cdot \mathbf{a}_{\text{noise}} \cdot \mathbf{a}_{\text{noise}}^T = \sigma_{\mathbf{a}}^2 \begin{pmatrix} \frac{p_x^2}{a^2} & \frac{p_x p_y}{a^2} & \frac{dtp_x}{a} & \frac{dtp_x}{a} & \frac{p_x}{a} & \frac{p_x}{a} & 0 & 0 \\ \frac{p_x p_y}{a^2} & \frac{p_y^2}{a^2} & \frac{dtp_y}{a} & \frac{dtp_y}{a} & \frac{p_y}{a} & \frac{p_y}{a} & 0 & 0 \\ \frac{dtp_x}{a} & \frac{dtp_y}{a} & dt^2 & dt^2 & dt & dt & 0 & 0 \\ \frac{dtp_x}{a} & \frac{dtp_y}{a} & dt^2 & dt^2 & dt & dt & 0 & 0 \\ \frac{p_x}{a} & \frac{p_y}{a} & dt & dt & 1 & 1 & 0 & 0 \\ \frac{p_x}{a} & \frac{p_y}{a} & dt & dt & 1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \end{pmatrix} \tag{22}$$

2.2 Via Yaw Rate

The system noise is partly determined by the yaw rate that the robot can experience.

$$\phi_z = \dot{\phi}_z dt \tag{23}$$

$$\dot{\phi}_{z_{\text{noise}}} = \begin{pmatrix} 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ \phi_z \\ \dot{\phi}_z \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ dt \\ 1 \end{pmatrix} \dot{\phi}_z \tag{24}$$

$$\mathbf{Q}_{\text{yaw}} = \sigma_{\text{yaw}}^2 \cdot \dot{\phi}_{z_{\text{noise}}} \cdot \dot{\phi}_{z_{\text{noise}}}^T = \sigma_{\text{yaw}}^2 \begin{pmatrix} 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & dt^2 & dt \\ 0 & 0 & 0 & 0 & 0 & 0 & dt & 1 \end{pmatrix} \tag{25}$$

2.3 Final System Noise Matrix

$$\mathbf{Q} = \mathbf{Q_j} + \mathbf{Q}_{\text{yaw}} = \begin{pmatrix} \frac{\sigma_{\mathbf{a}}^2 p_x^2}{a^2} & \frac{\sigma_{\mathbf{a}}^2 p_x p_y}{a^2} & \frac{\sigma_{\mathbf{a}}^2 dt p_x}{a} & \frac{\sigma_{\mathbf{a}}^2 dt p_x}{a} & \frac{\sigma_{\mathbf{a}}^2 p_x}{a} & \frac{\sigma_{\mathbf{a}}^2 p_x}{a} & 0 & 0 \\ \frac{\sigma_{\mathbf{a}}^2 p_x p_y}{a^2} & \frac{\sigma_{\mathbf{a}}^2 p_y^2}{a^2} & \frac{\sigma_{\mathbf{a}}^2 dt p_y}{a} & \frac{\sigma_{\mathbf{a}}^2 dt p_y}{a} & \frac{\sigma_{\mathbf{a}}^2 p_y}{a} & \frac{\sigma_{\mathbf{a}}^2 p_y}{a} & 0 & 0 \\ \frac{\sigma_{\mathbf{a}}^2 dt p_x}{a} & \frac{\sigma_{\mathbf{a}}^2 dt p_y}{a} & \sigma_{\mathbf{a}}^2 dt^2 & \sigma_{\mathbf{a}}^2 dt^2 & \sigma_{\mathbf{a}}^2 dt & \sigma_{\mathbf{a}}^2 dt & 0 & 0 \\ \frac{\sigma_{\mathbf{a}}^2 dt p_x}{a} & \frac{\sigma_{\mathbf{a}}^2 dt p_y}{a} & \sigma_{\mathbf{a}}^2 dt^2 & \sigma_{\mathbf{a}}^2 dt^2 & \sigma_{\mathbf{a}}^2 dt & \sigma_{\mathbf{a}}^2 dt & 0 & 0 \\ \frac{\sigma_{\mathbf{a}}^2 p_x}{a} & \frac{\sigma_{\mathbf{a}}^2 p_y}{a} & \sigma_{\mathbf{a}}^2 dt & \sigma_{\mathbf{a}}^2 dt & \sigma_{\mathbf{a}}^2 & \sigma_{\mathbf{a}}^2 & 0 & 0 \\ \frac{\sigma_{\mathbf{a}}^2 p_x}{a} & \frac{\sigma_{\mathbf{a}}^2 p_y}{a} & \sigma_{\mathbf{a}}^2 dt & \sigma_{\mathbf{a}}^2 dt & \sigma_{\mathbf{a}}^2 & \sigma_{\mathbf{a}}^2 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & \sigma_{\dot{\phi}_z}^2 dt^2 & \sigma_{\dot{\phi}_z}^2 dt \\ 0 & 0 & 0 & 0 & 0 & 0 & \sigma_{\dot{\phi}_z}^2 dt & \sigma_{\dot{\phi}_z}^2 \end{pmatrix} \tag{26}$$