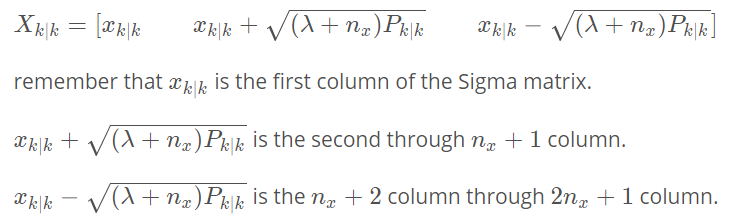
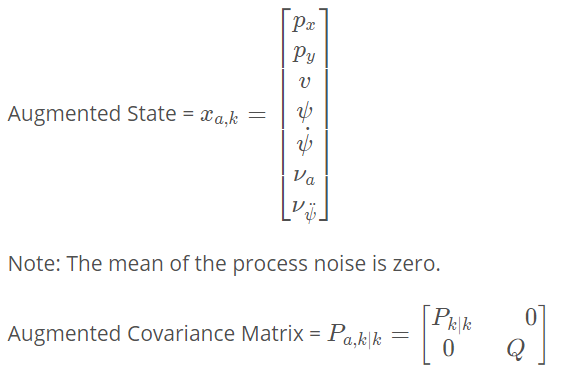
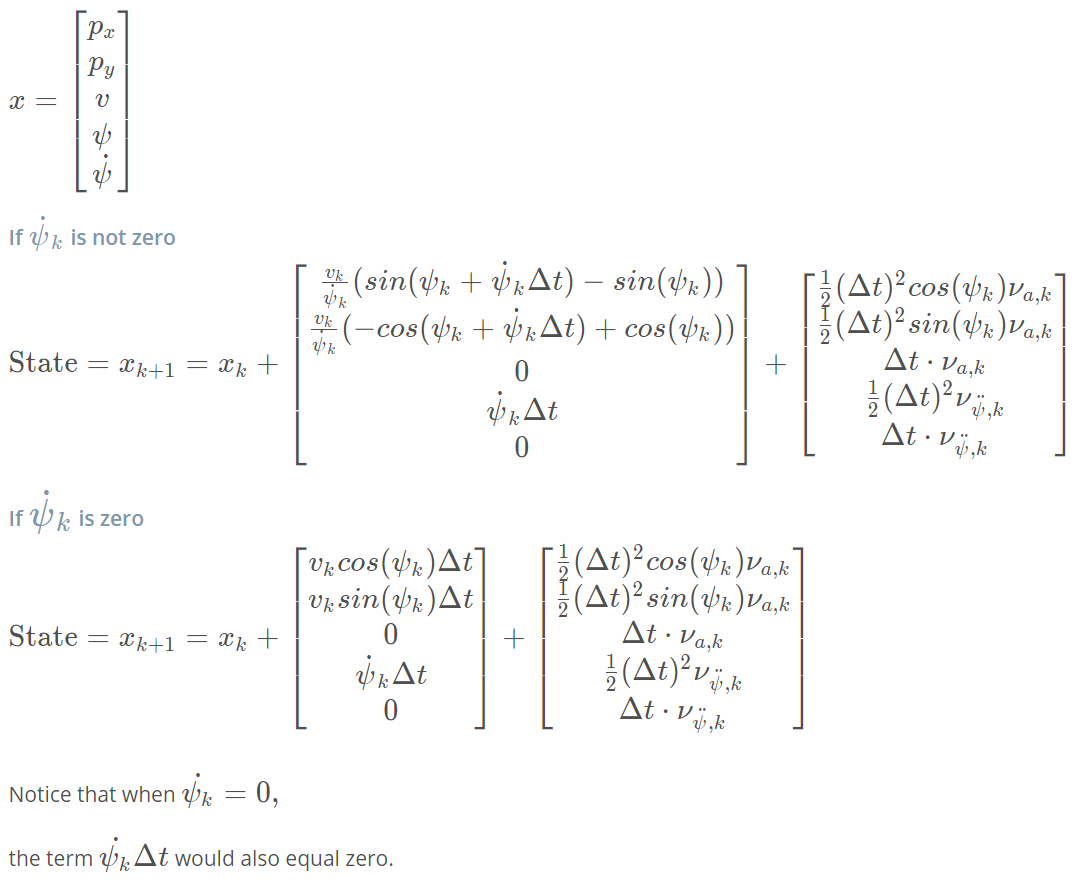


# Generate x,P Sigma Points:

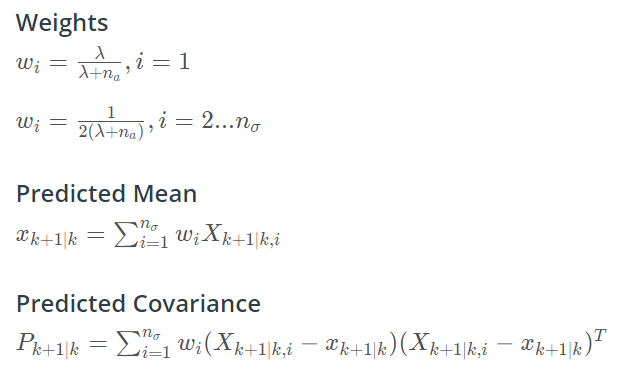




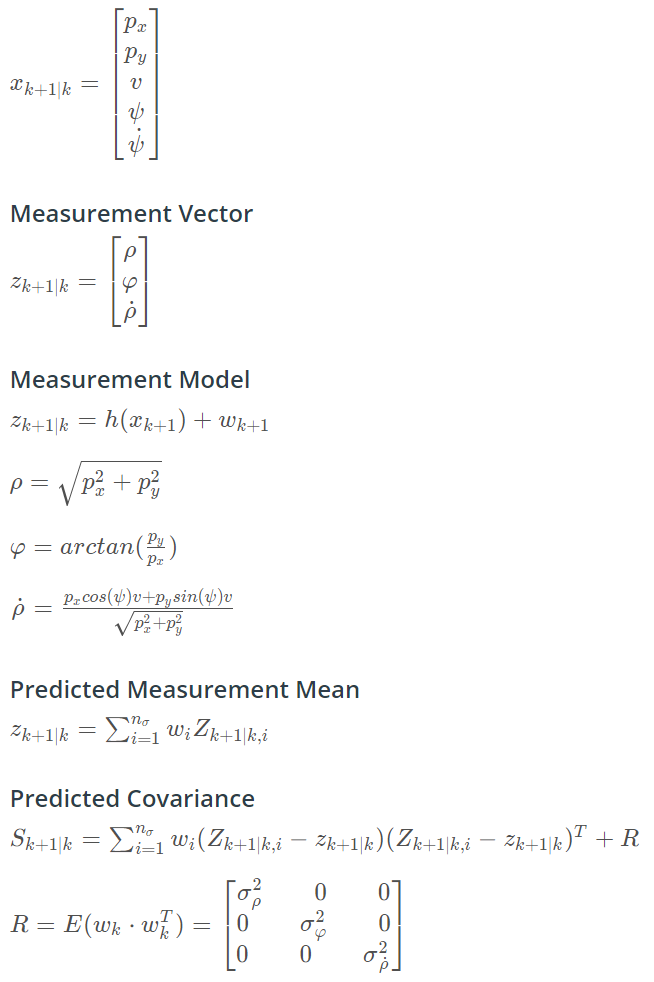
# Predict x,P Sigma Points:



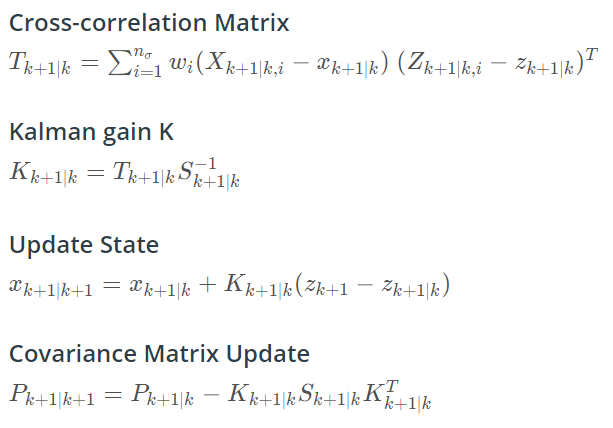
# Predict x,P Mean and Cov:



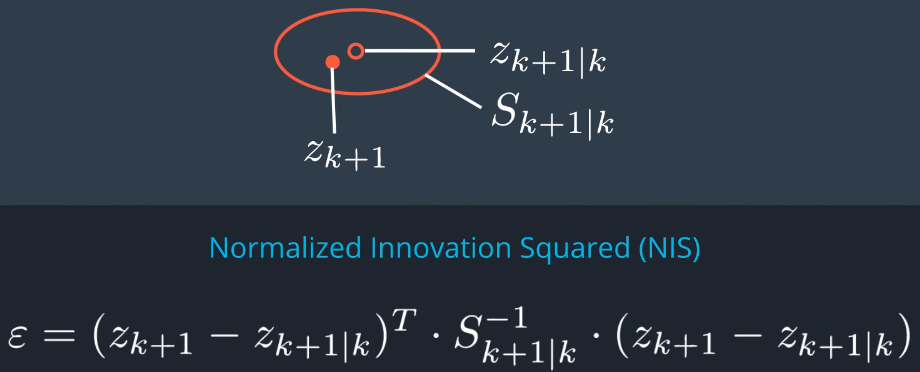
# Measurement Predict:



# Measurement Update State:



# NIS:





**sensor\_type, rho\_measured, phi\_measured, rhodot\_measured, timestamp, x\_groundtruth, y\_groundtruth, vx\_groundtruth, vy\_groundtruth, yaw\_groundtruth, yawrate\_groundtruth**.

**sensor\_type, x\_measured, y\_measured, timestamp, x\_groundtruth, y\_groundtruth, vx\_groundtruth, vy\_groundtruth, yaw\_groundtruth, yawrate\_groundtruth**