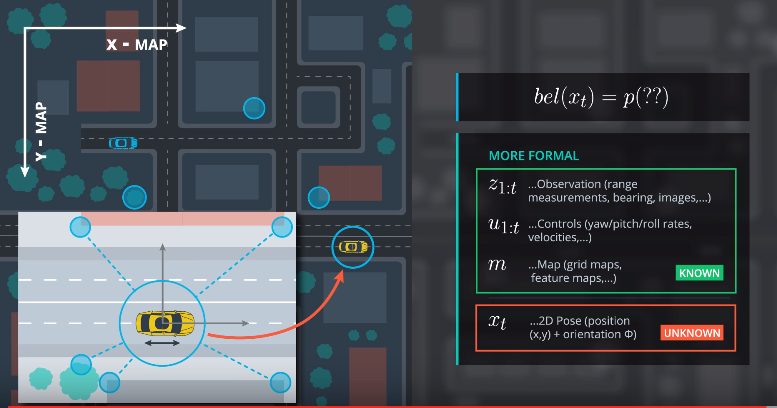
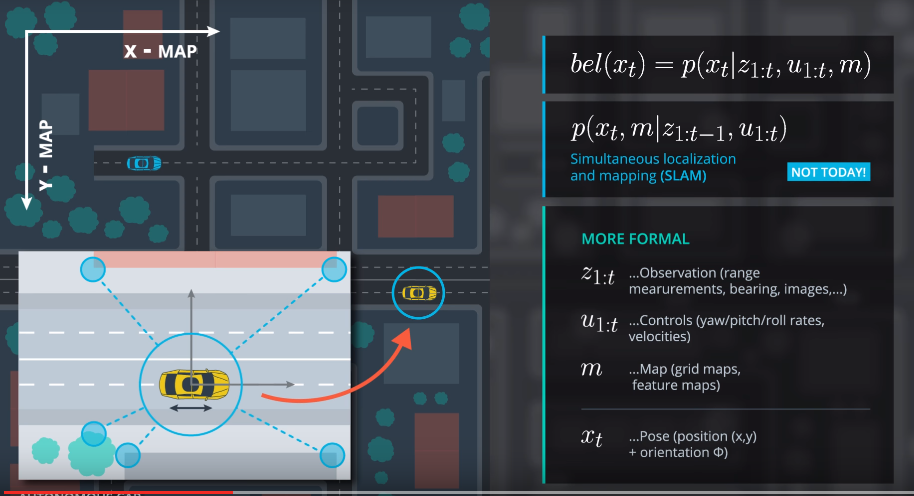
Markov Localization

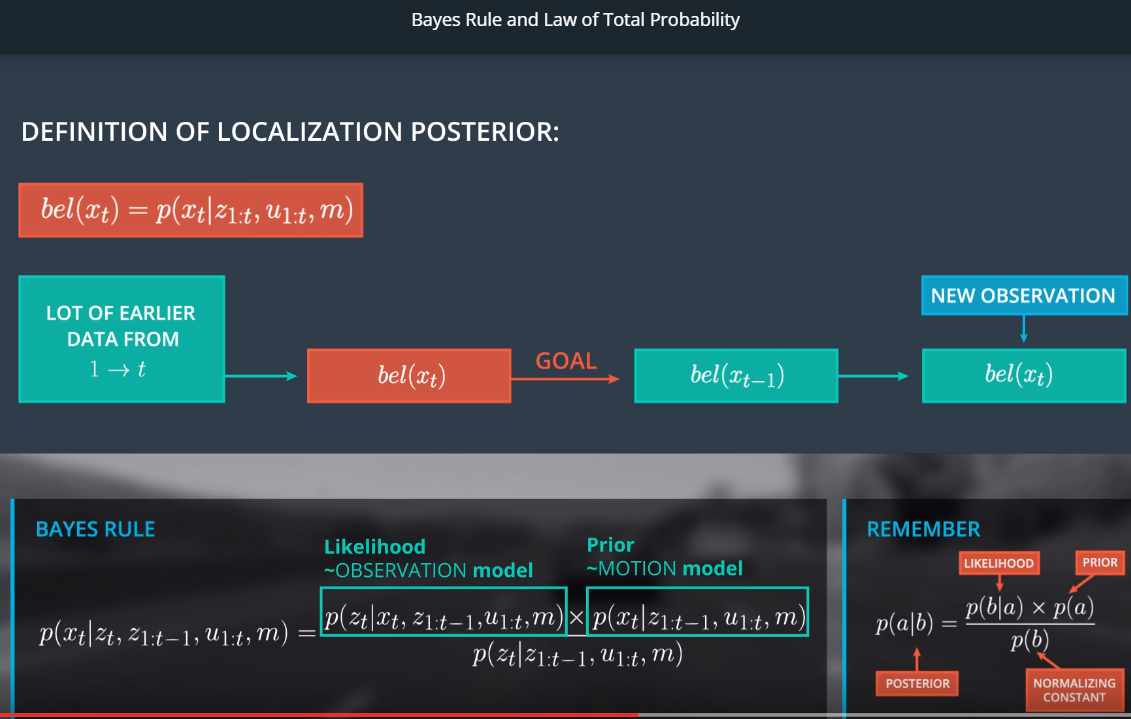
11.2 localization Posterior

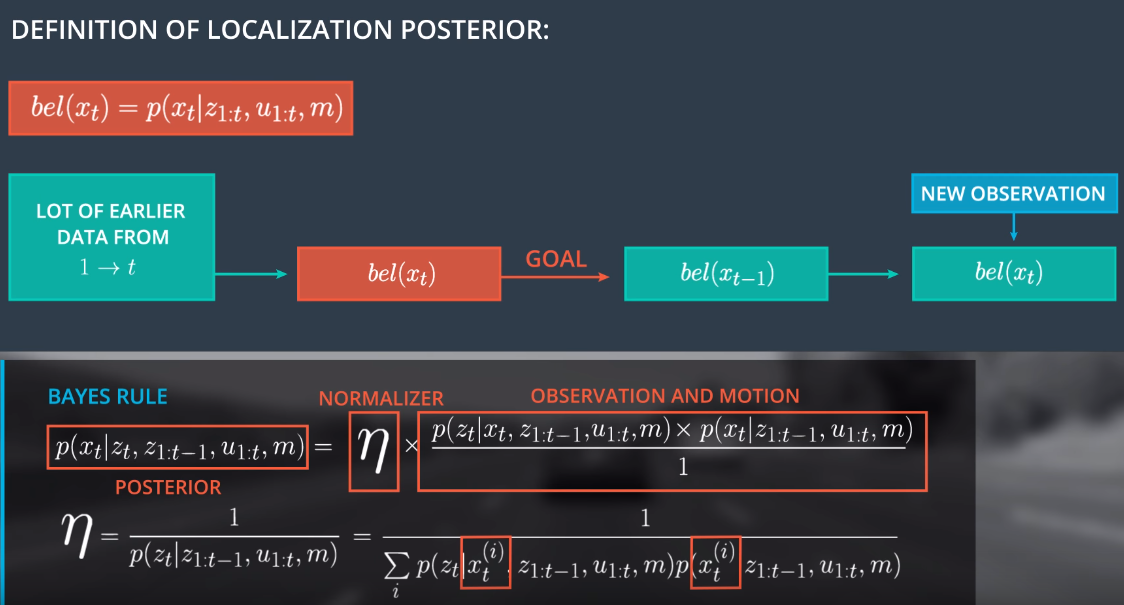


Simultaneous localization and mapping ( SLAM)

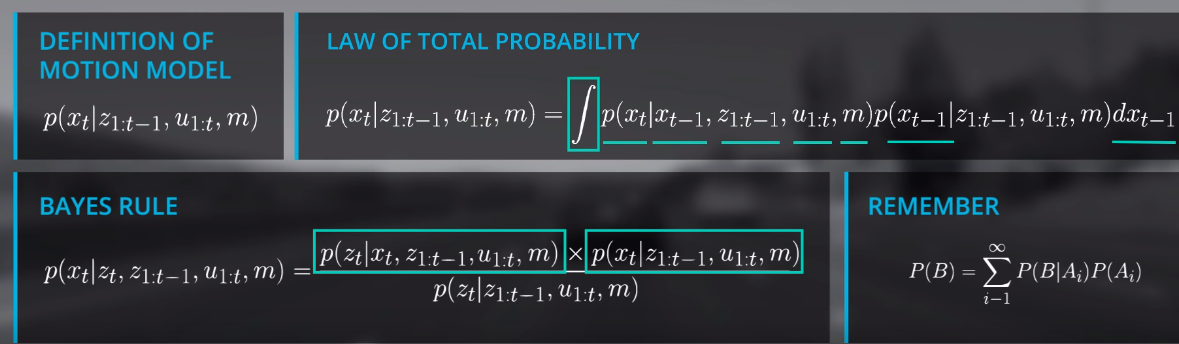


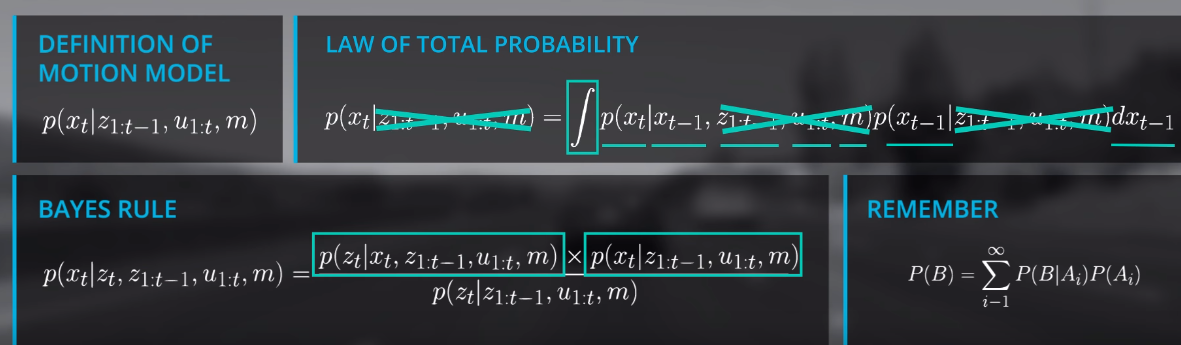
11.9 Bayes Rule and law of total Probability

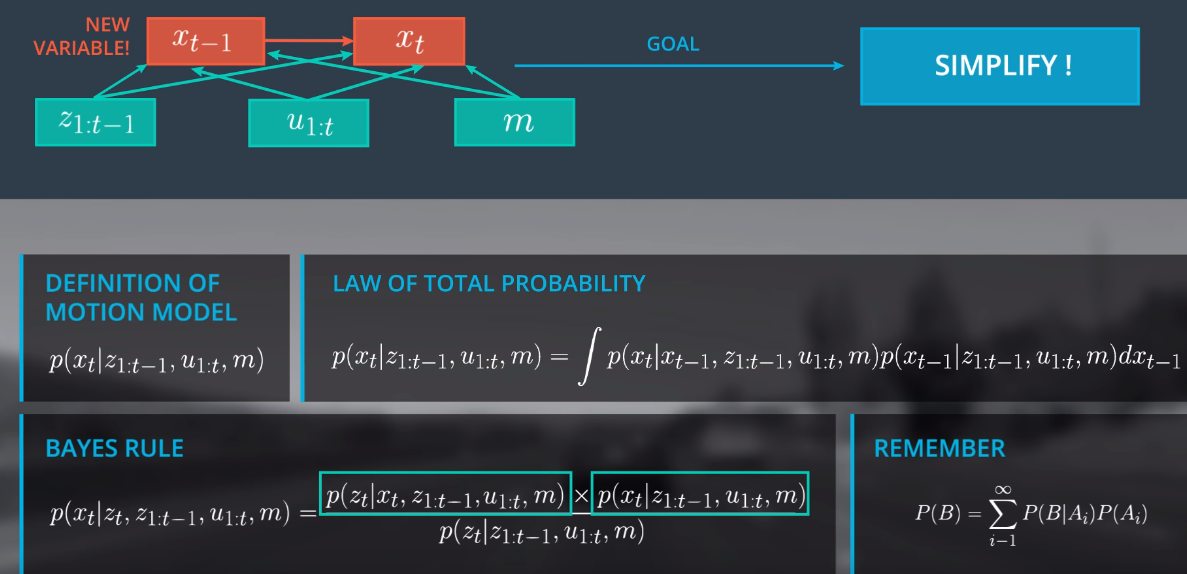




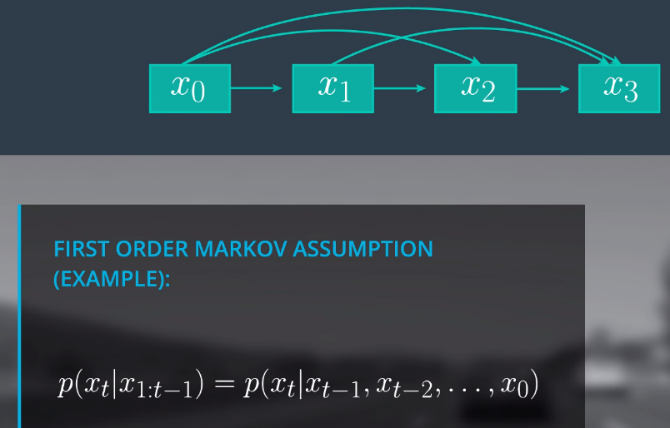
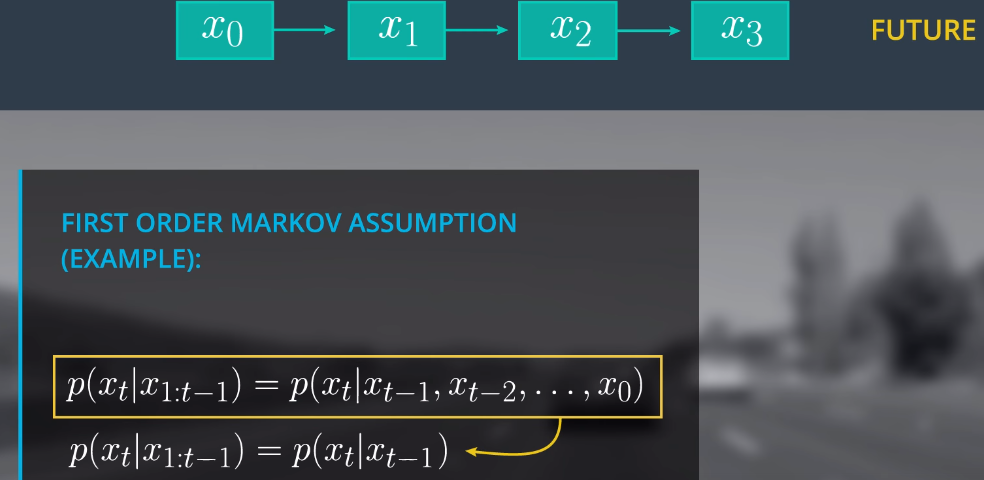
11.11



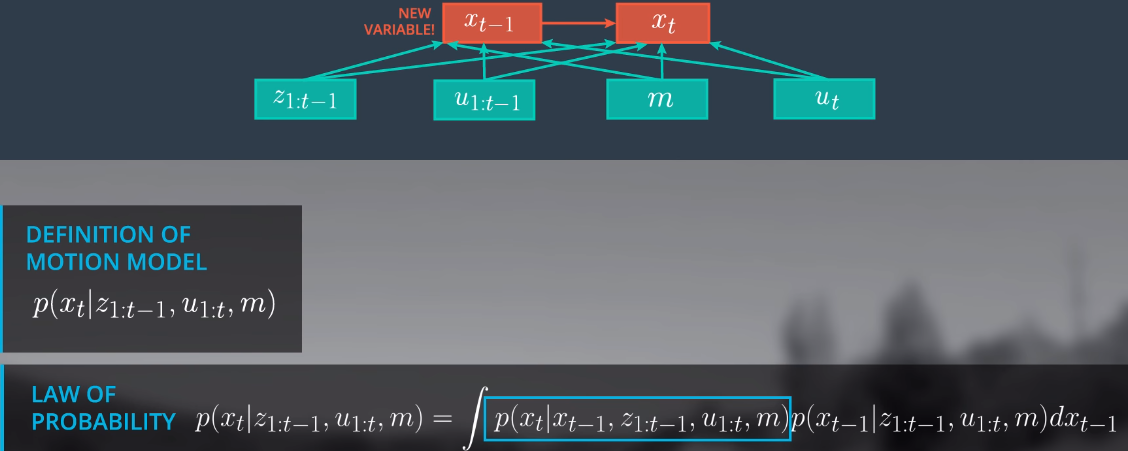


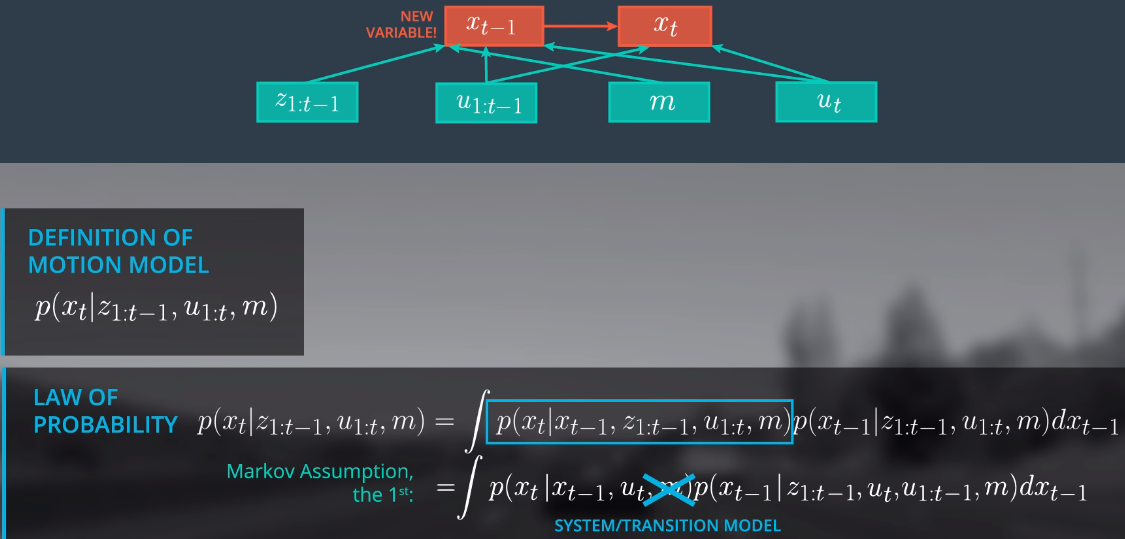


11.13 Markov Assumption for Motion Model

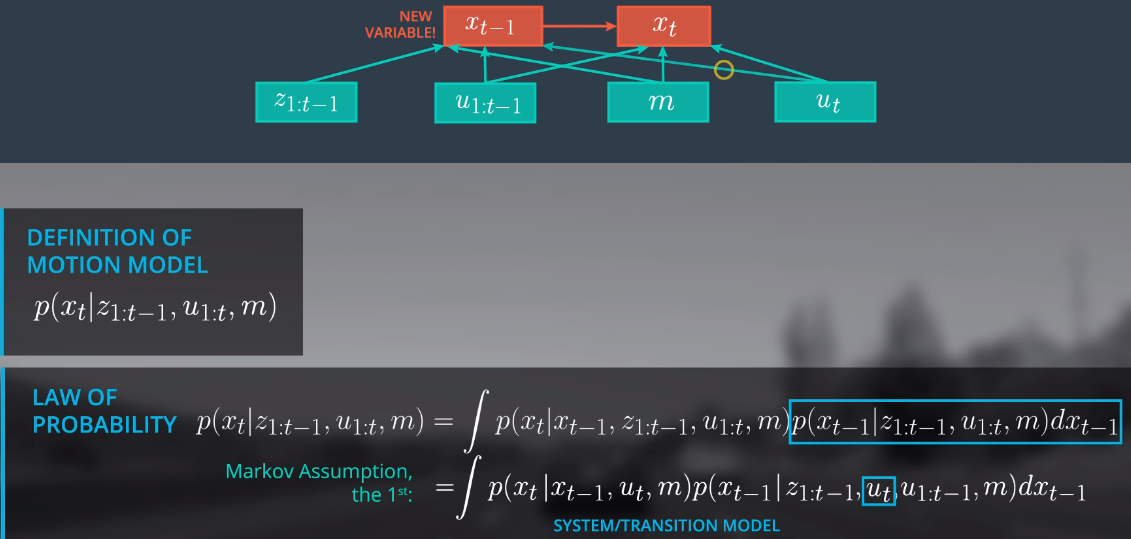


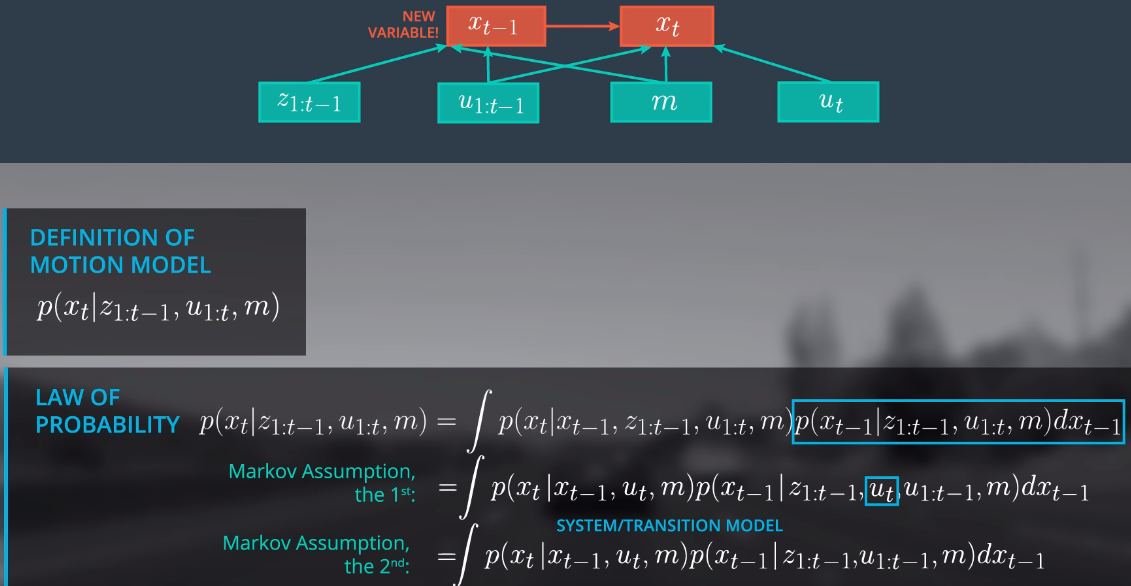
1st Assumption,



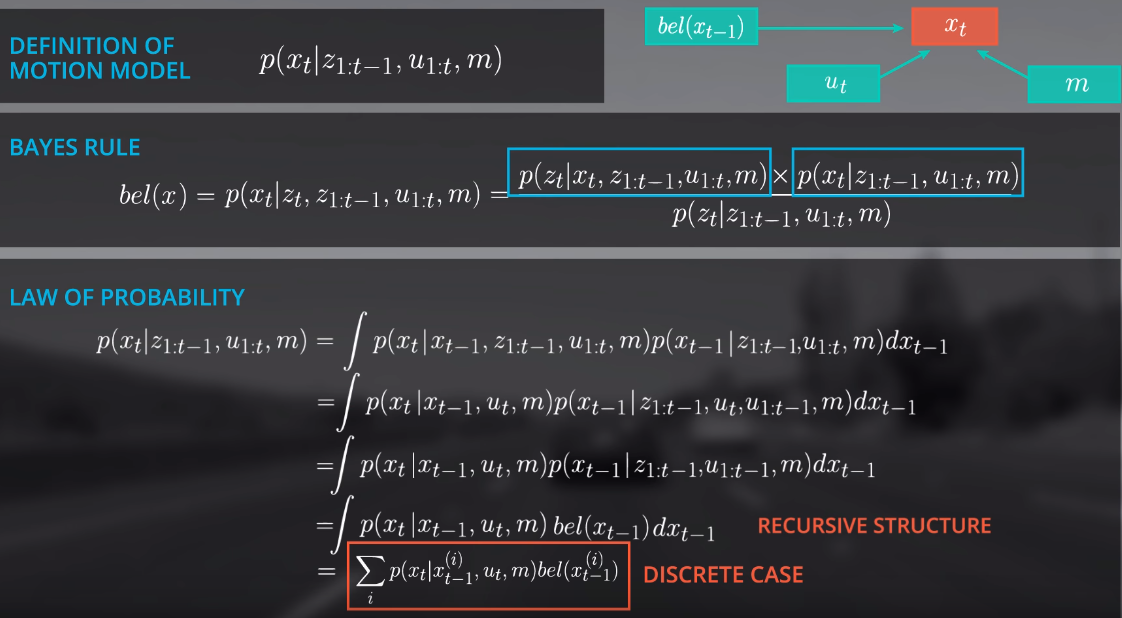


2nd Assumption



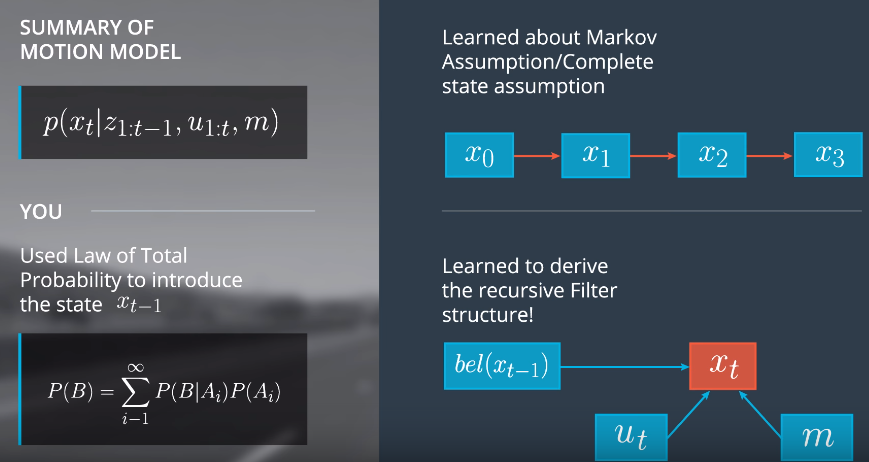


11.15 Recursive Structure

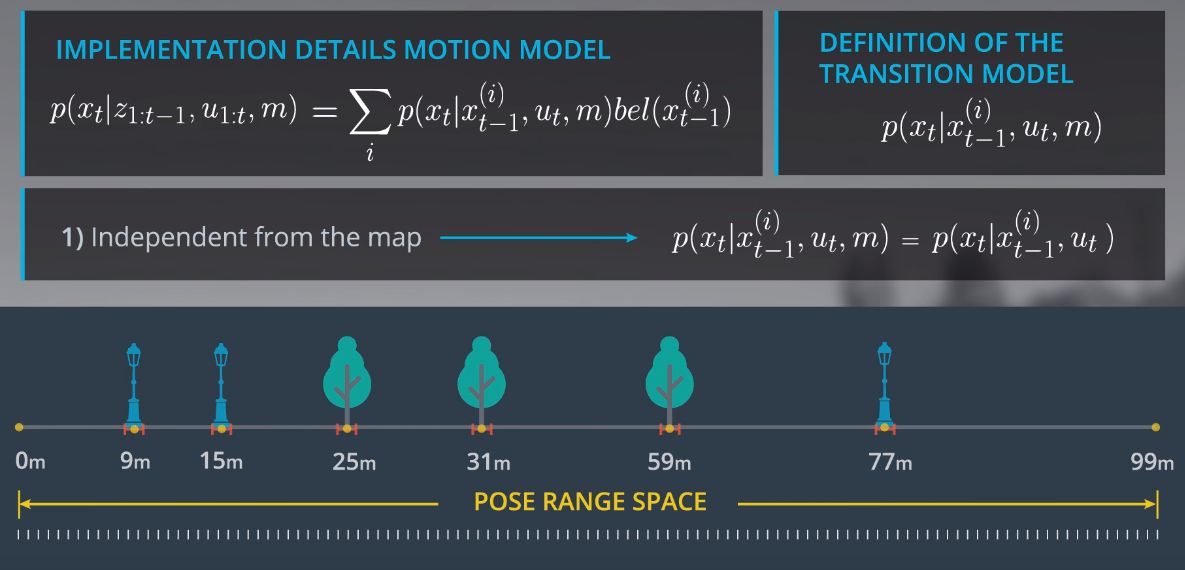


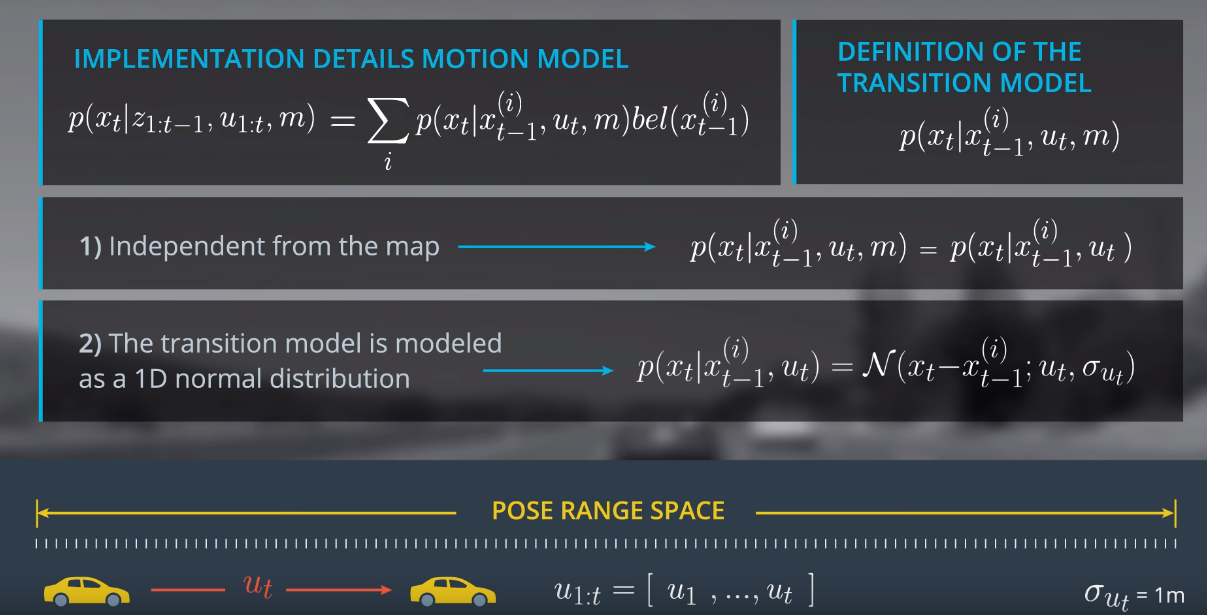
Use GPS to get coarse init x(t=0)

Recursive structure !

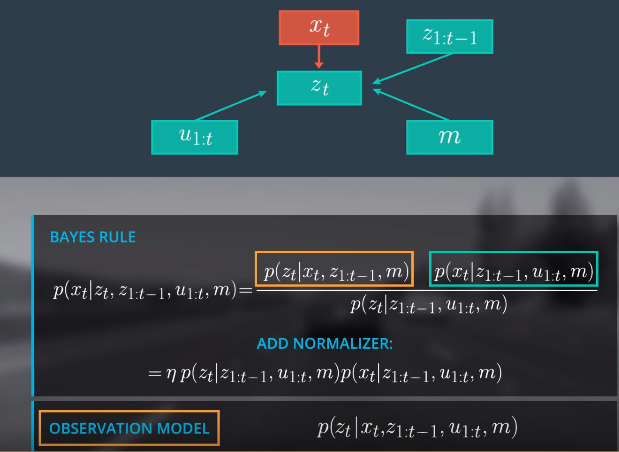


11.16 implement Motion Model

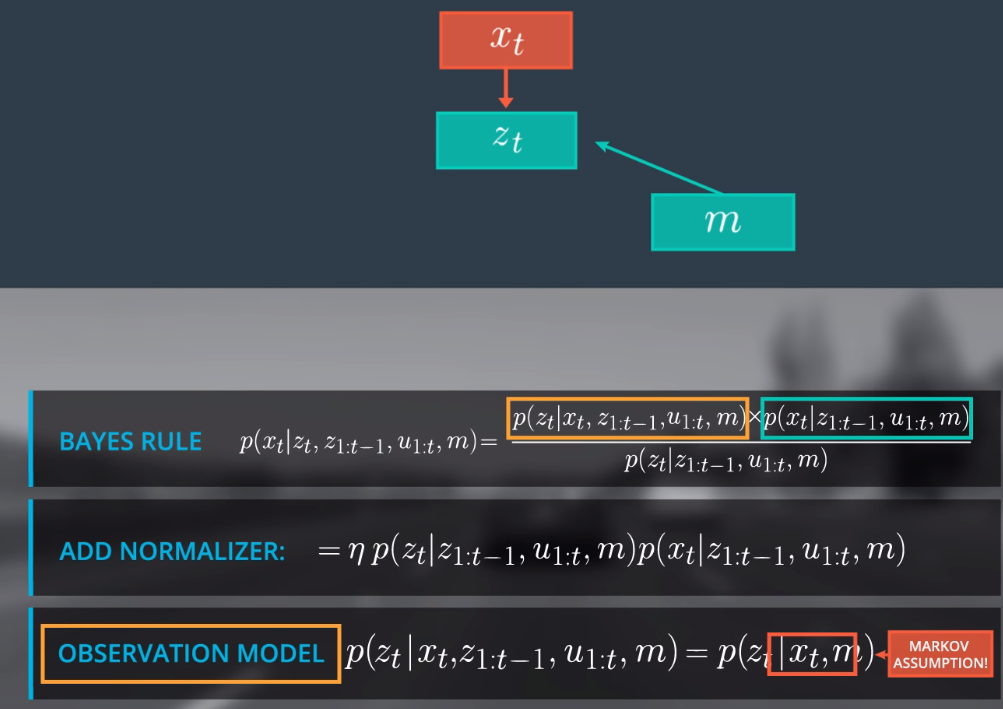




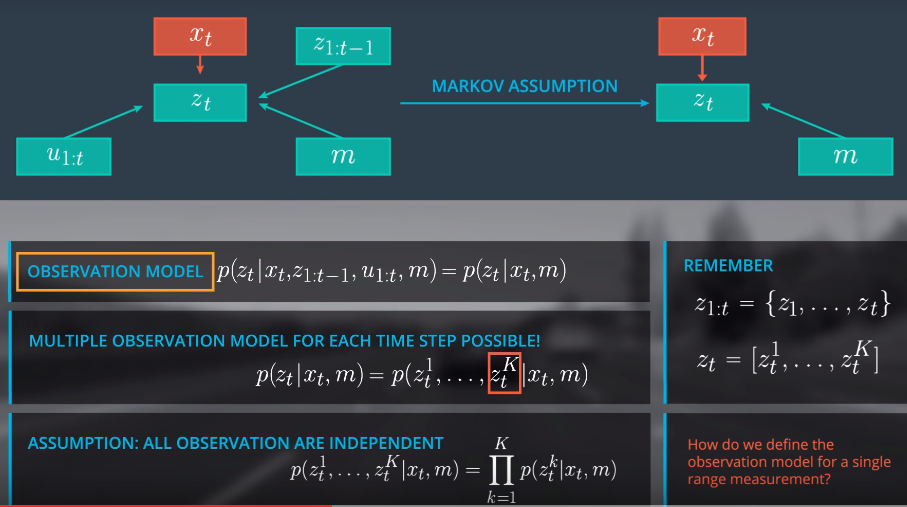
11.21 Observation Model



11.22 Markov Assumption for Observation Model



Multiple Observation model



1-D example observation model

