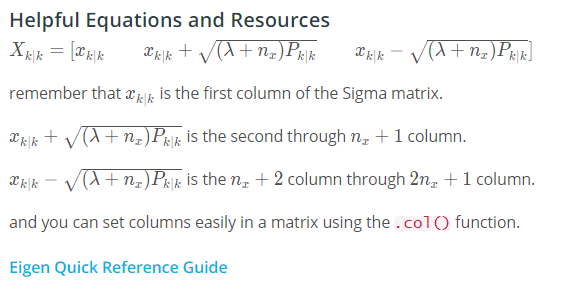
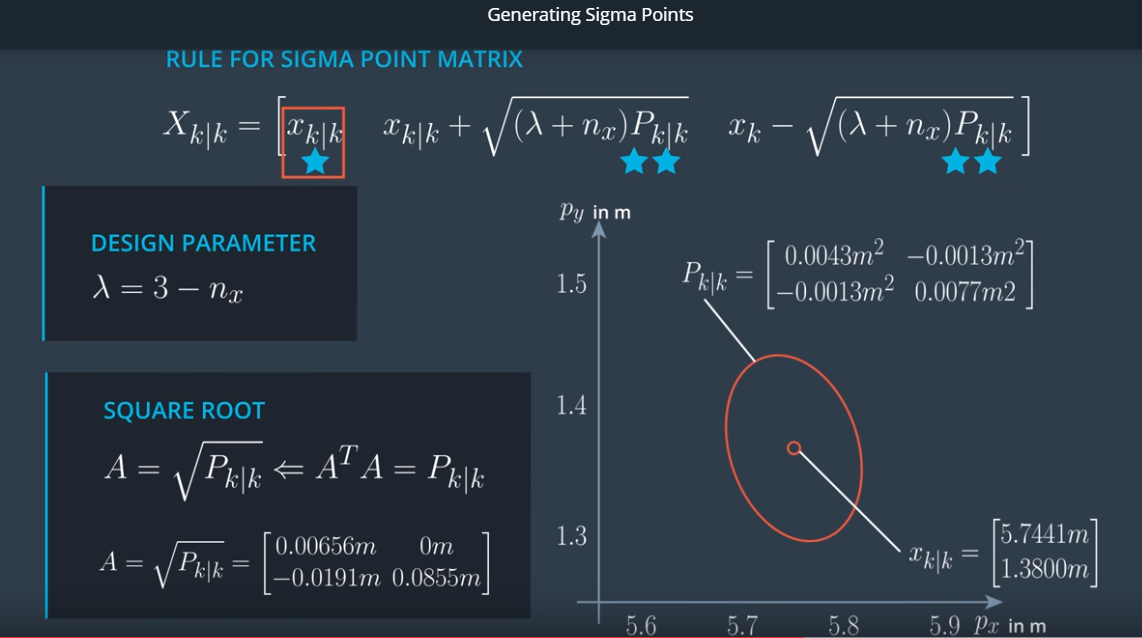
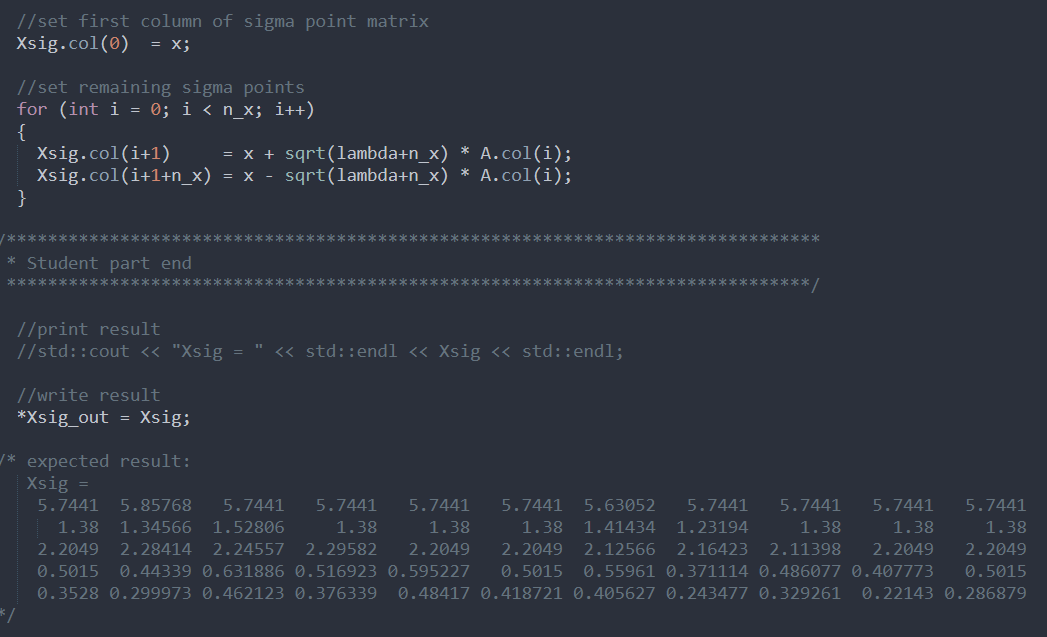
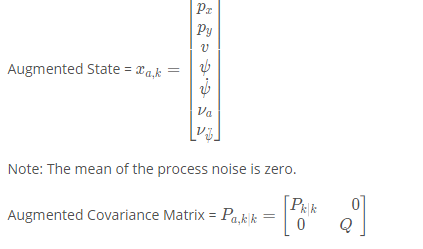
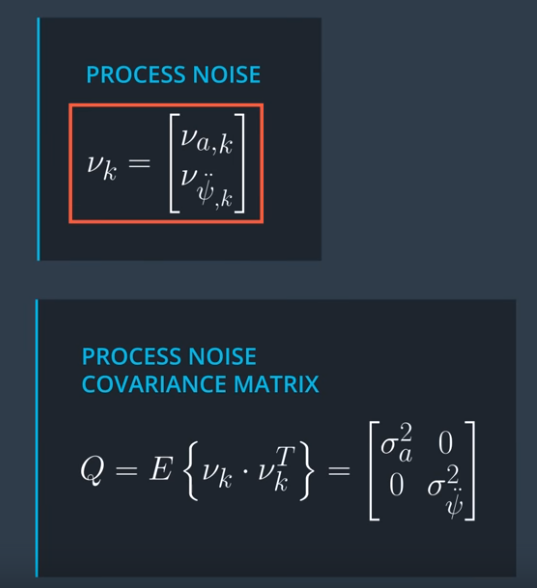
**7.13 sigma points generation (t = k)**

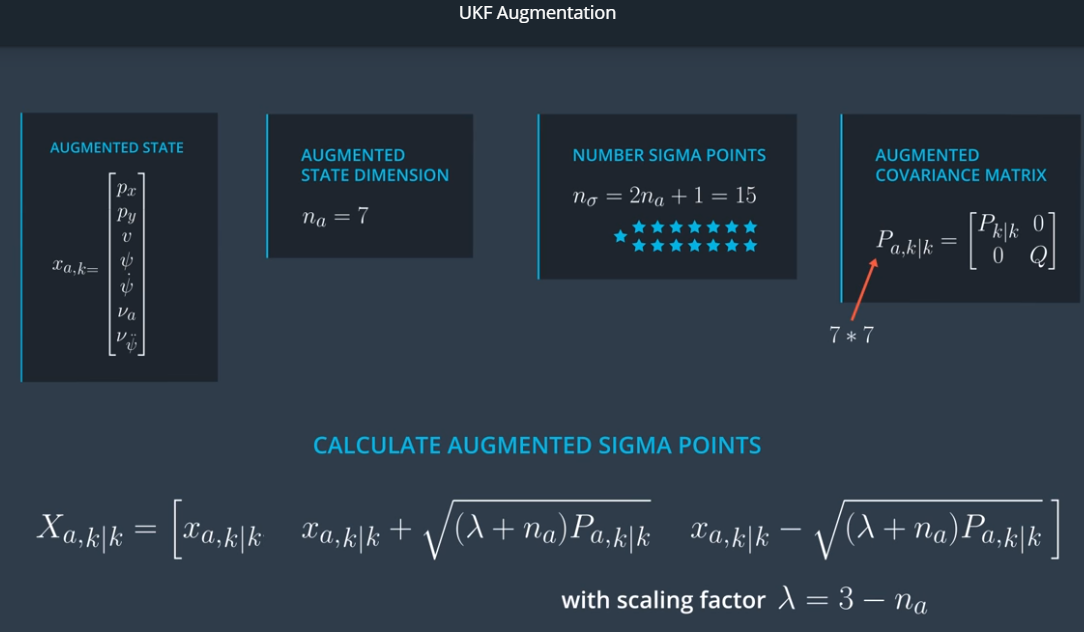


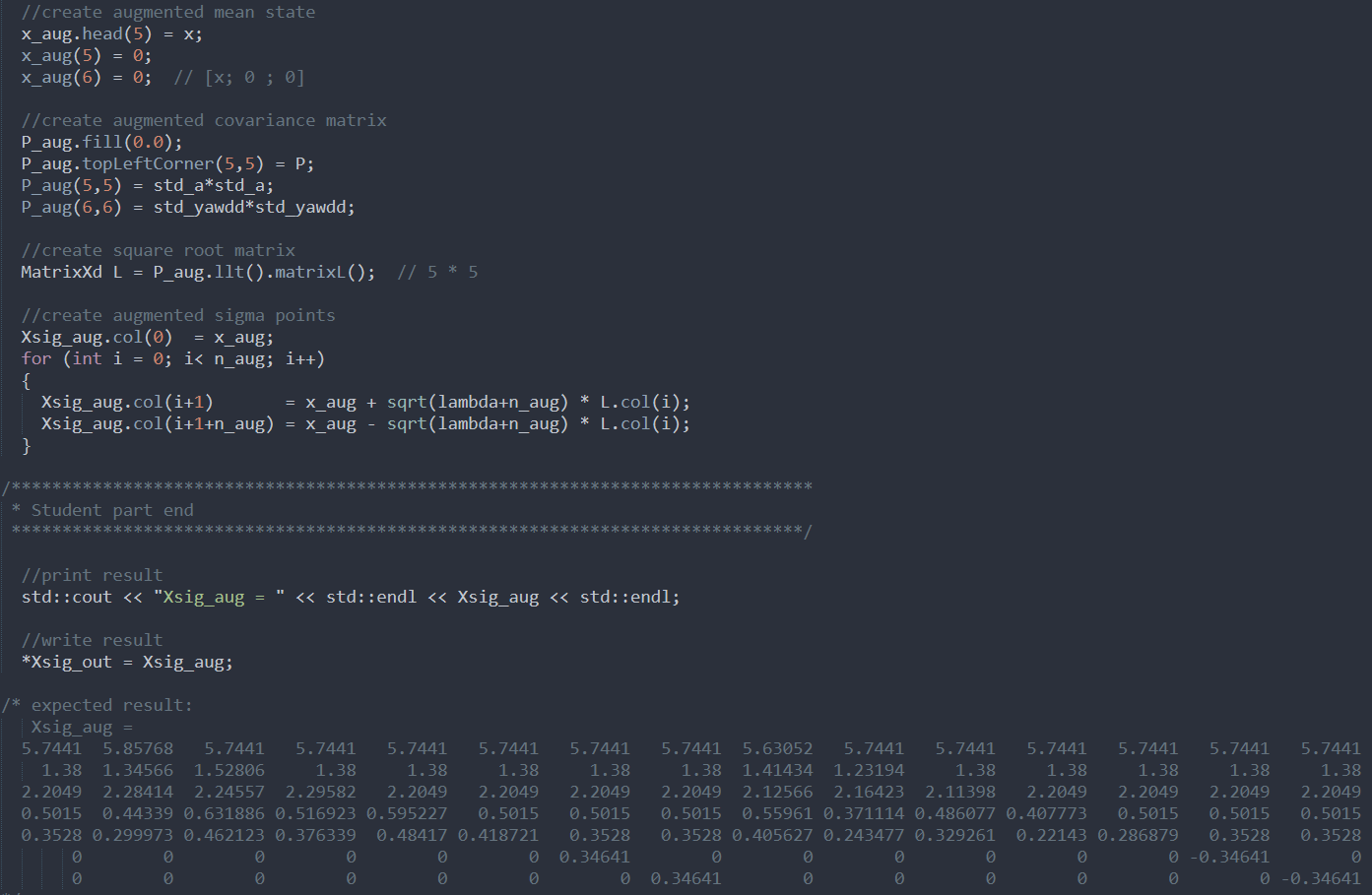




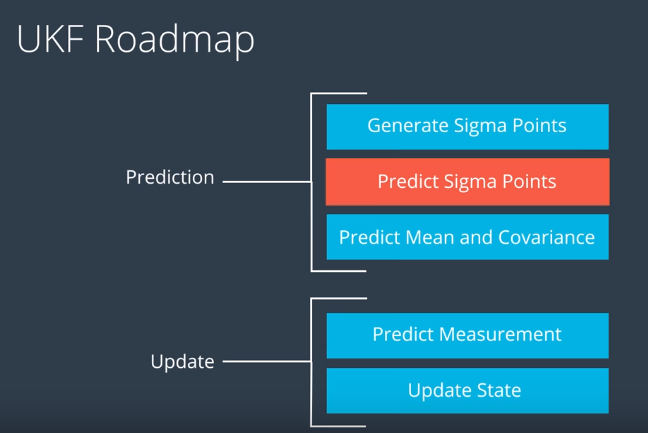
**7.16 Augmentation ( with motion acceleration noise)**

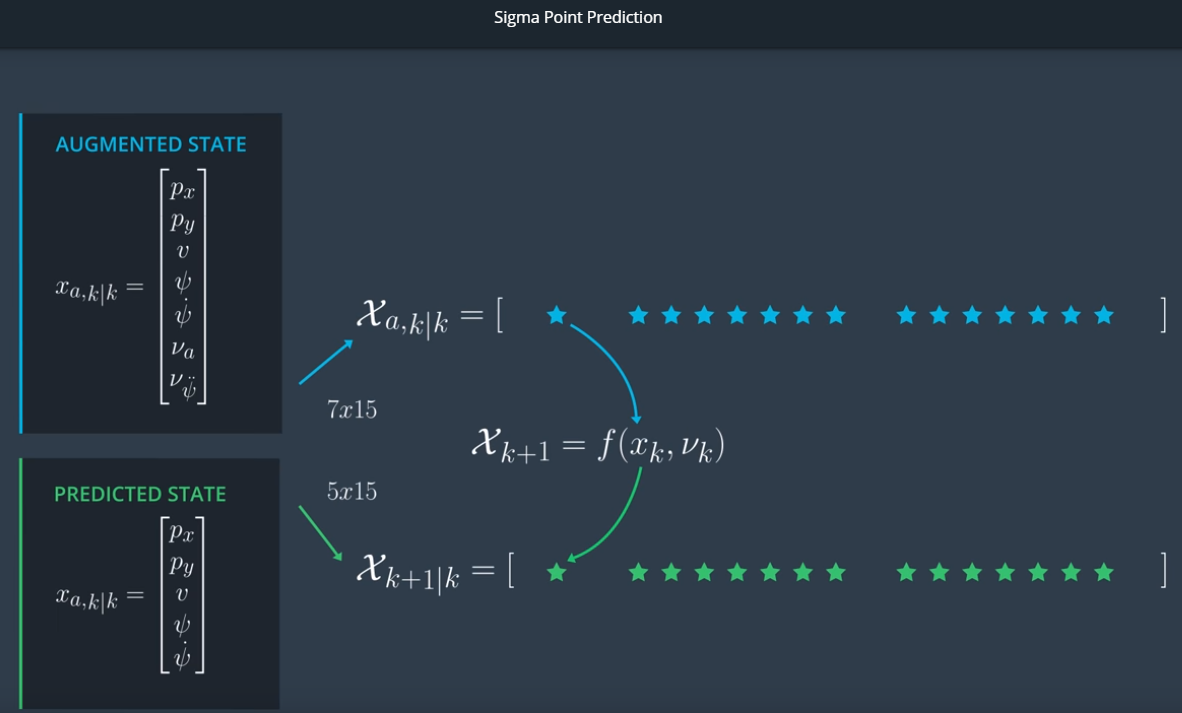
 

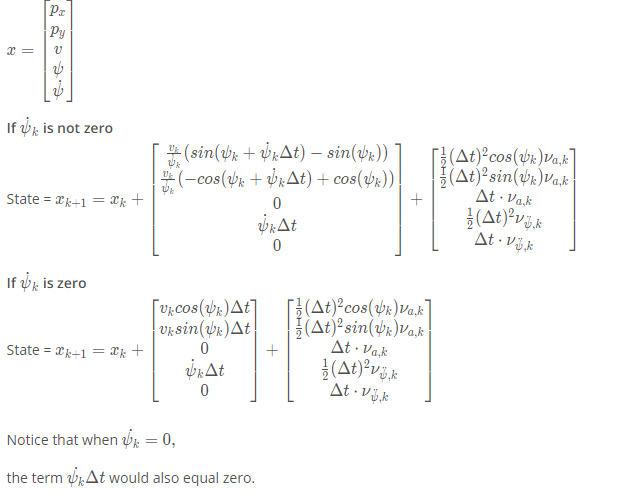




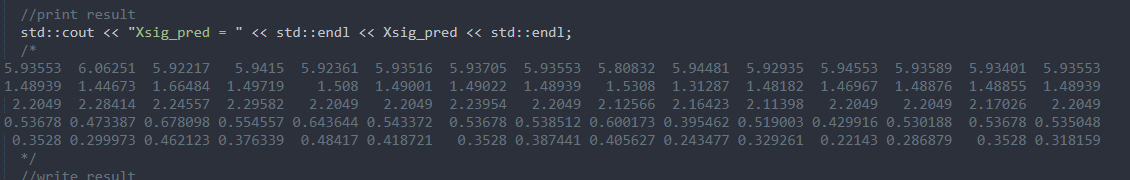
**7.19 Sigma point prediction**



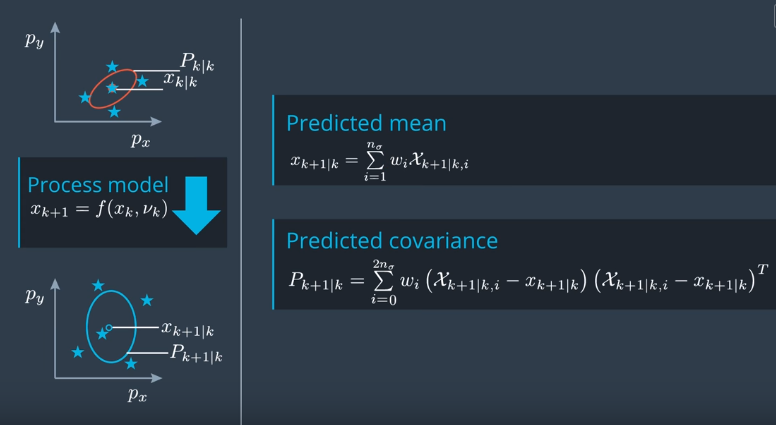


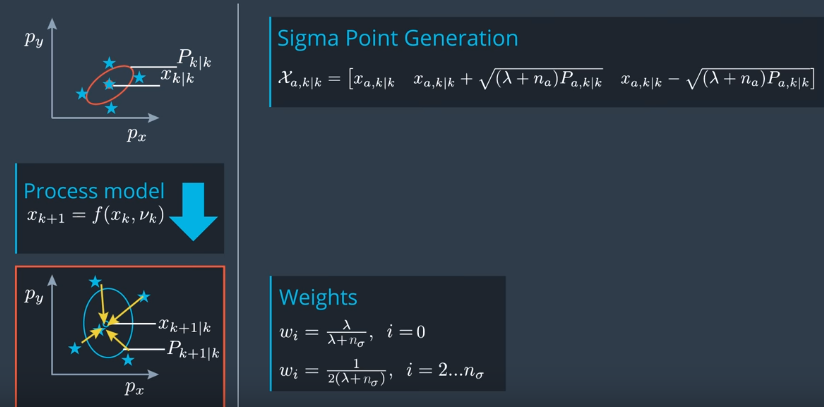


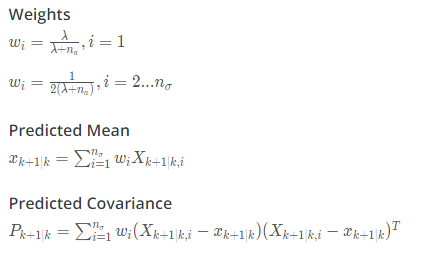


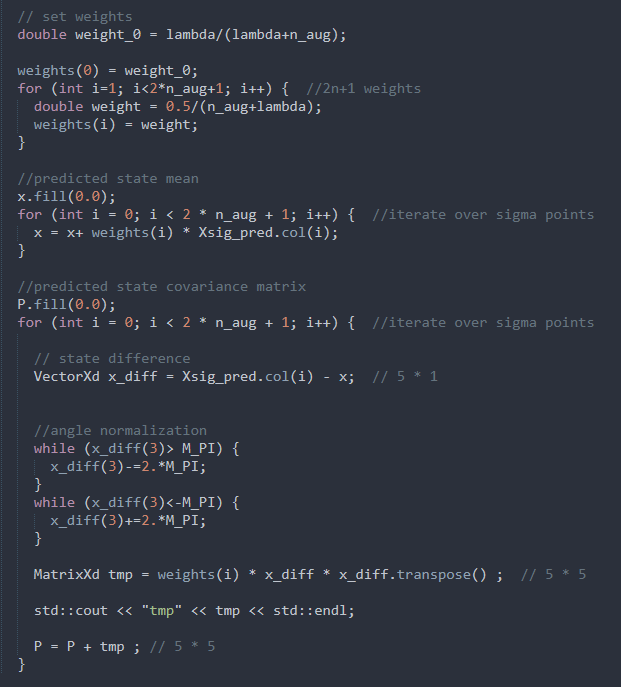


**7.22 Predict mean and covariance**

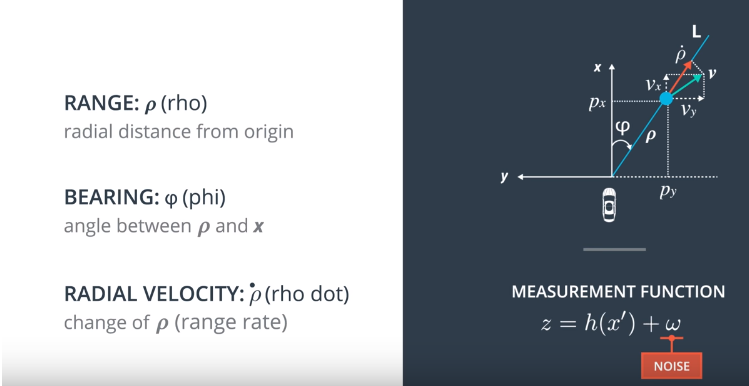


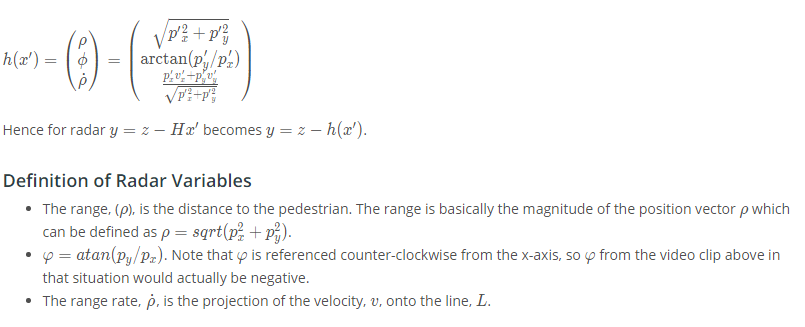


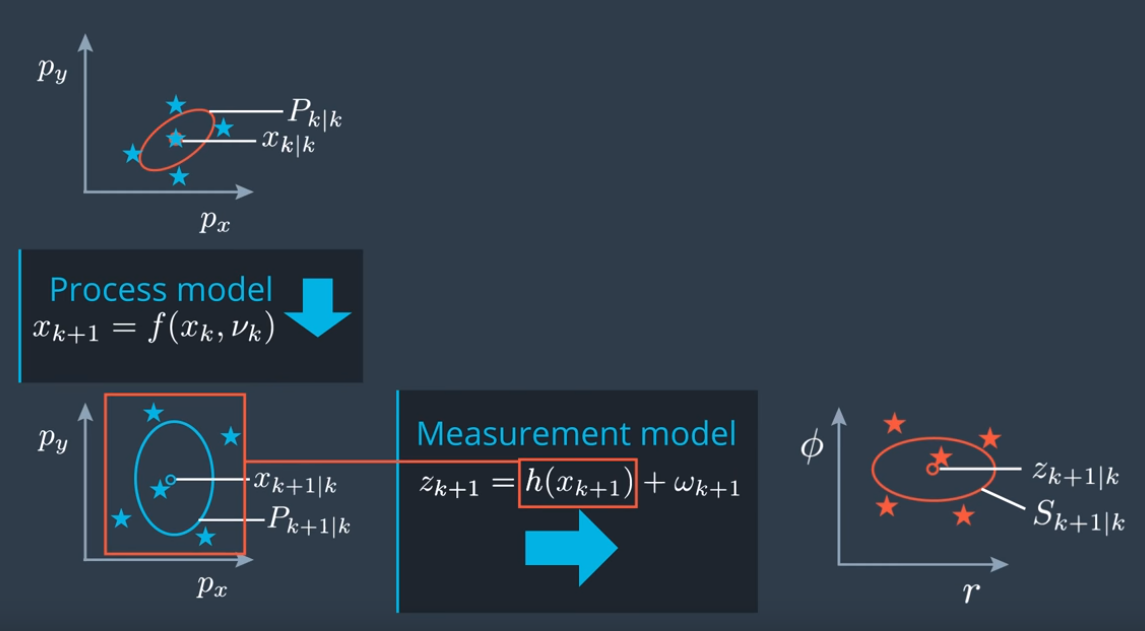


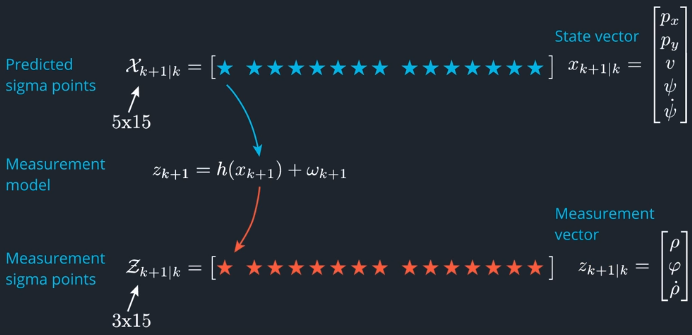


**7.25 Update : Measurement prediction ( Radar ?)**

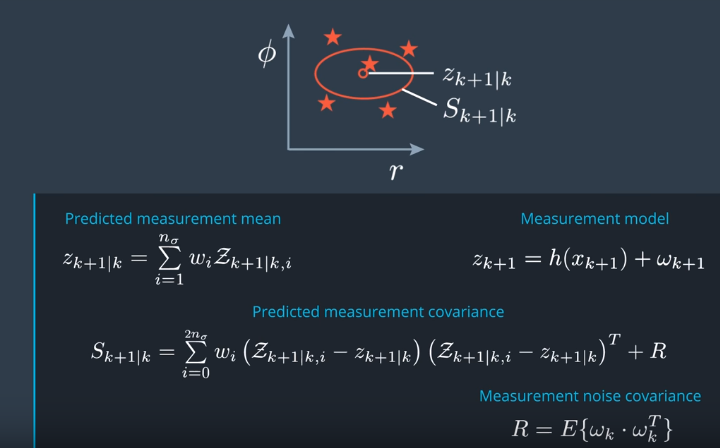


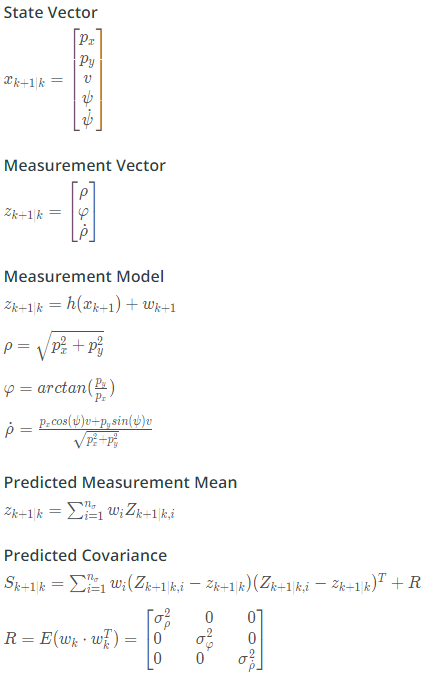


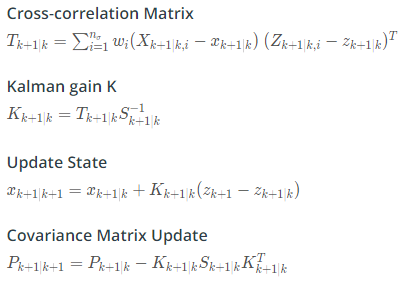


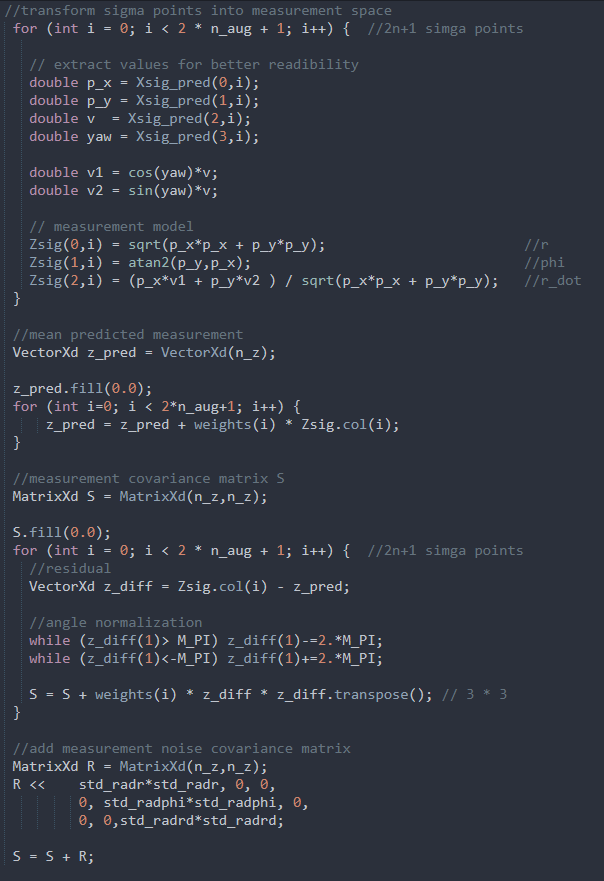


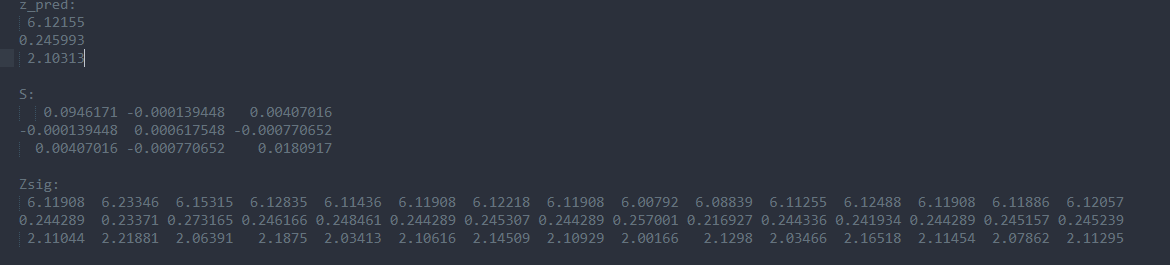
**Notice !! since noise in measurement is additive, so we can get rid of Augmentation of X(k+1), but add R of measurement noise covariance directly**



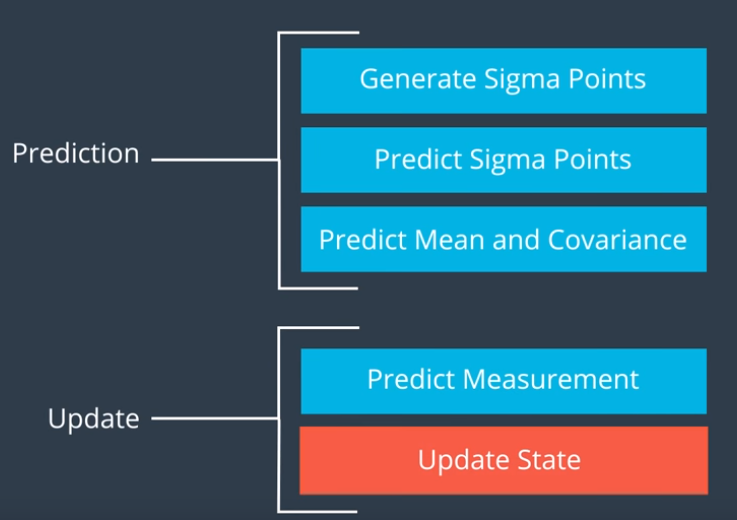


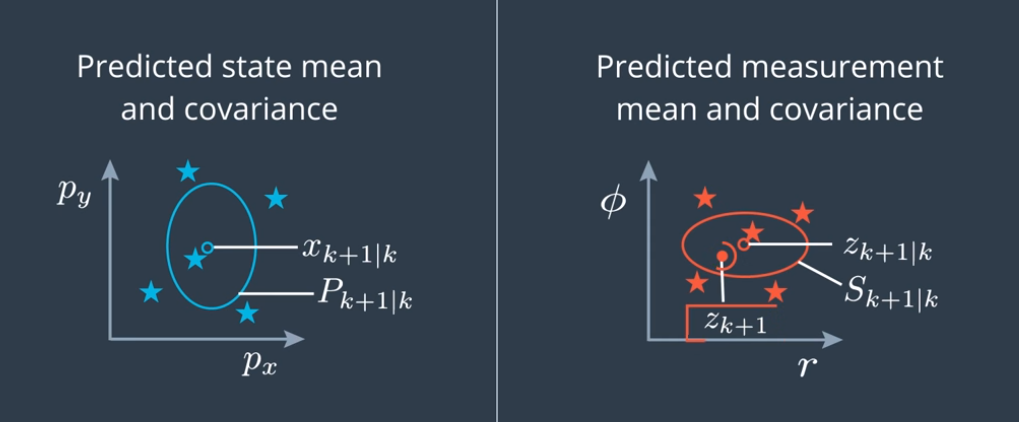


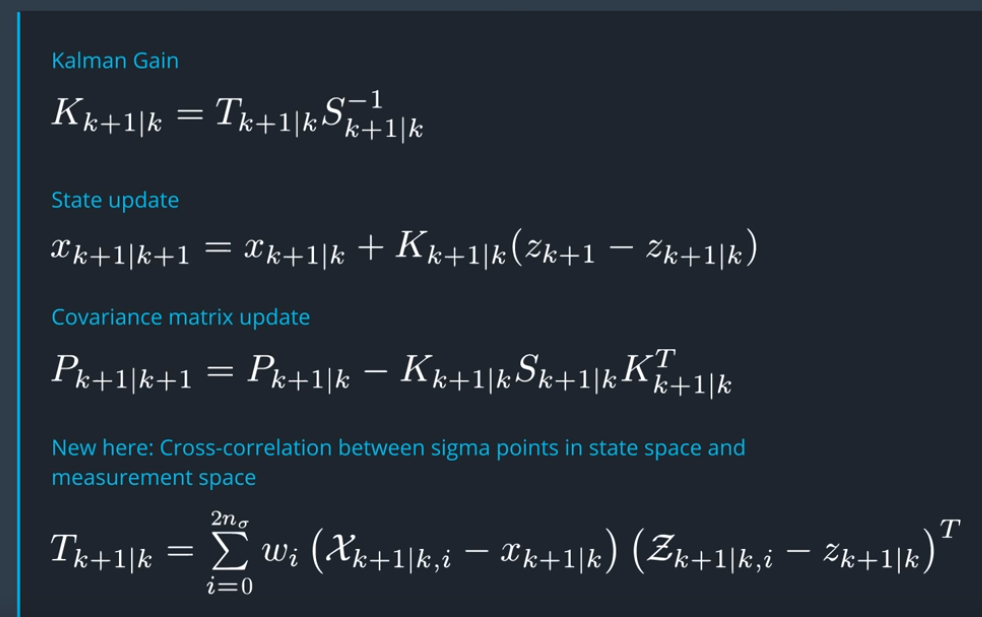


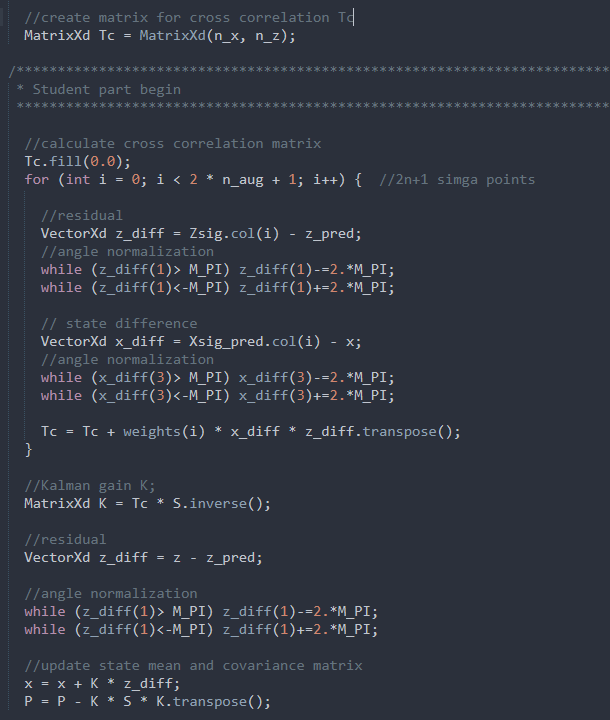


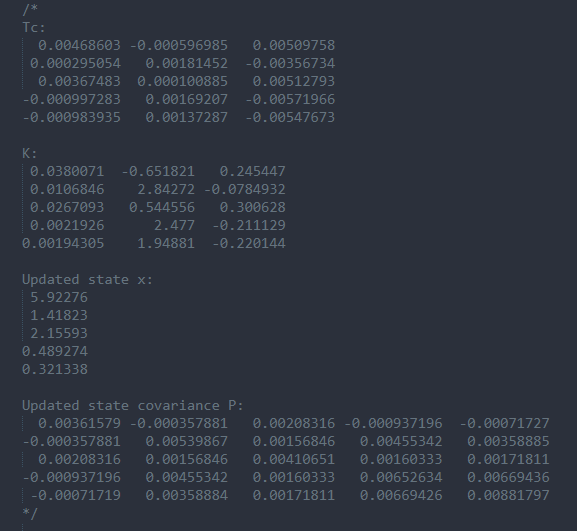
**7.28 Update : state vector ( Radar )**











**7.31 Noise evaluation for all Bayesian filter**

