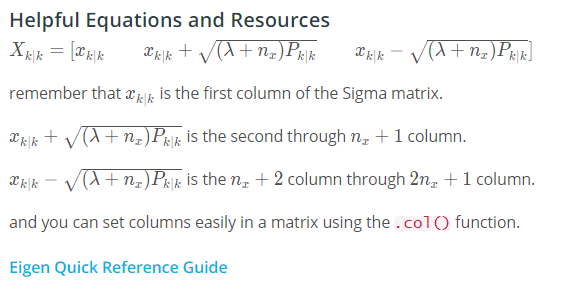
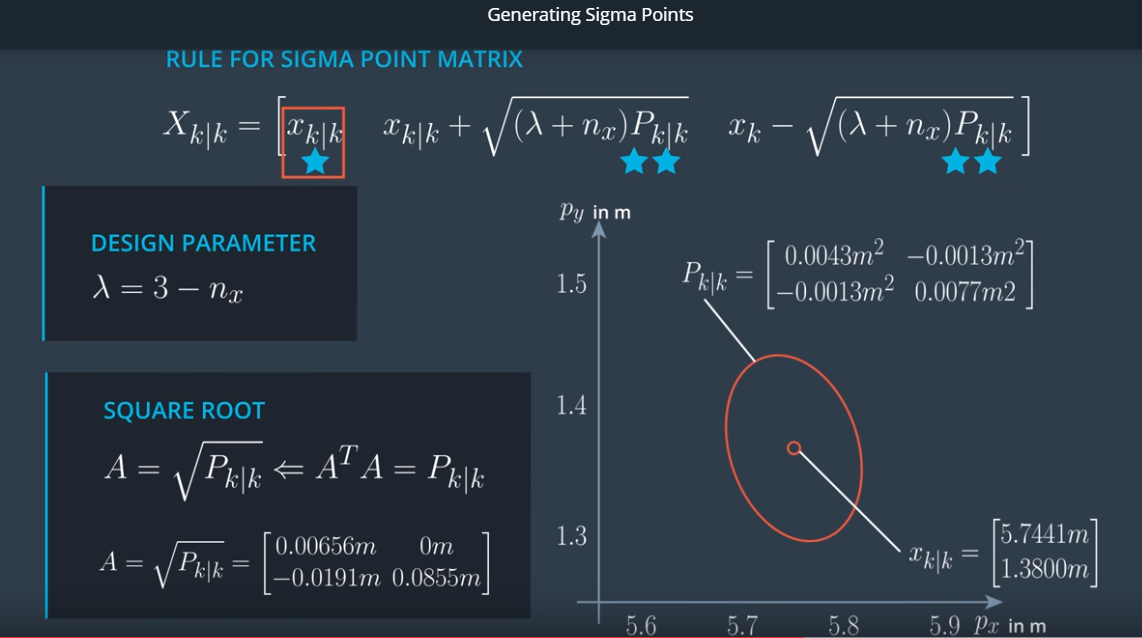
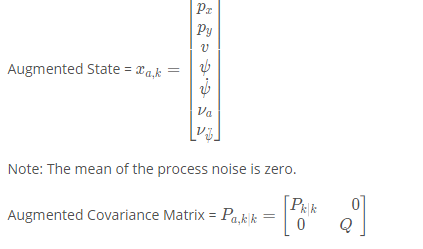
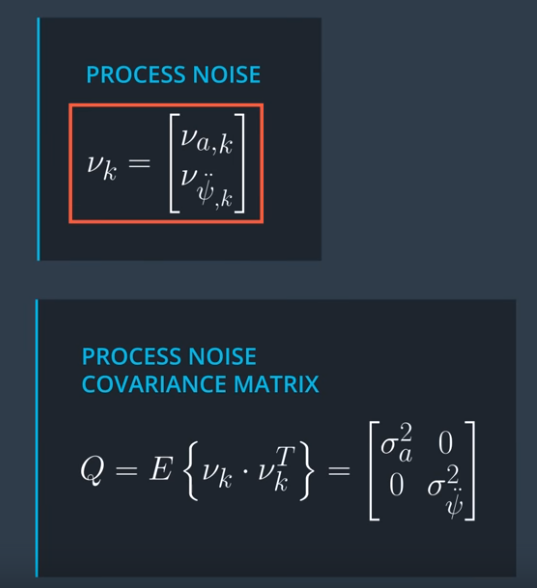
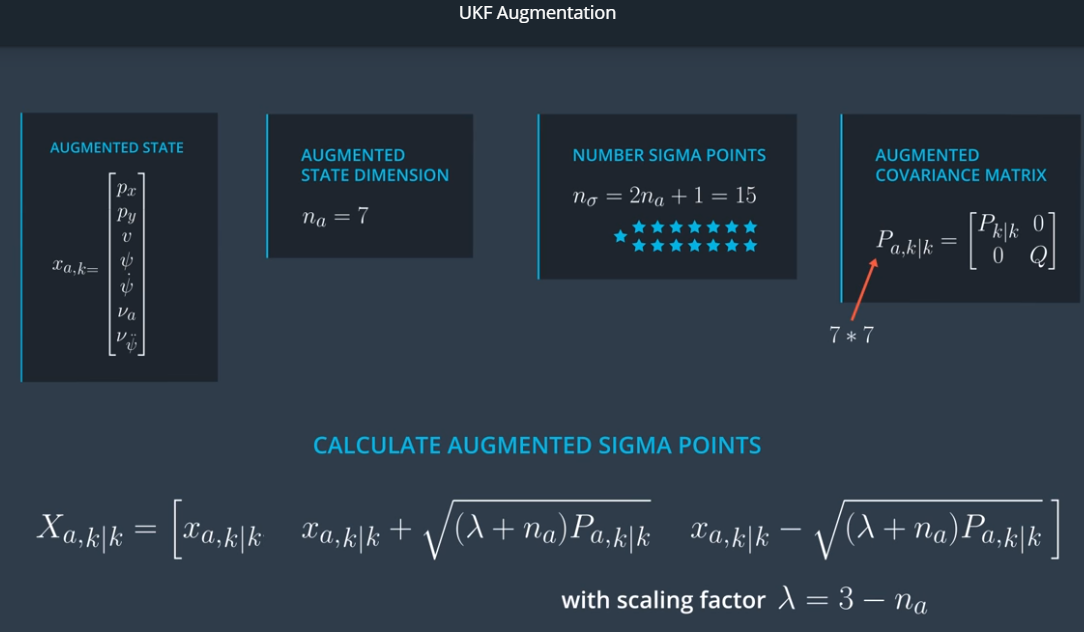
**7.13 sigma points generation (t = k)**



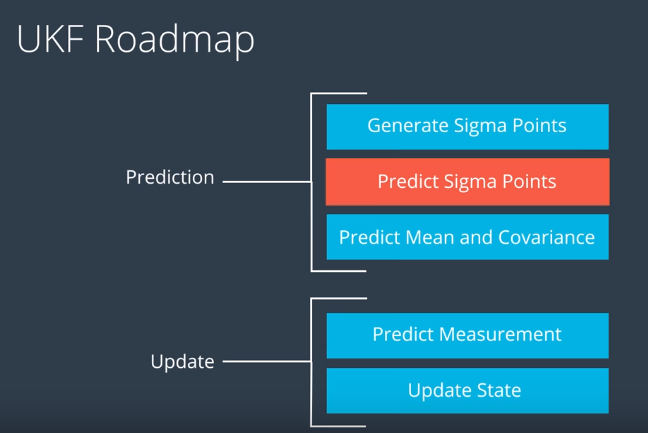


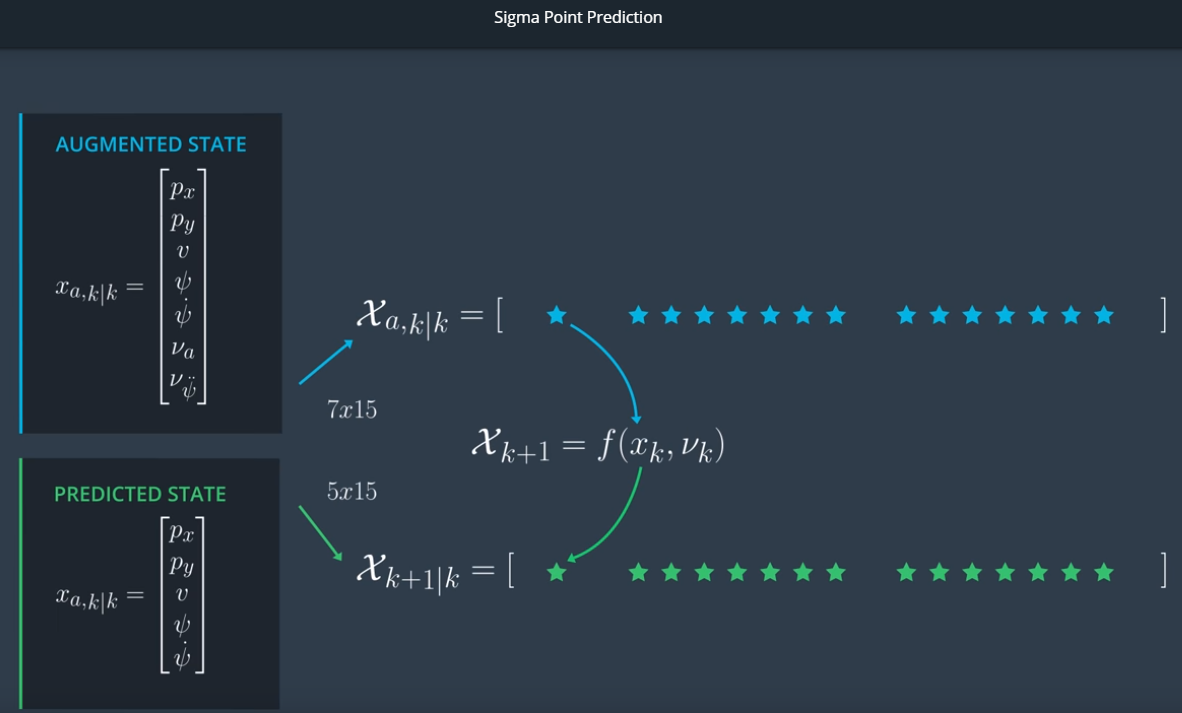
**7.16 Augmentation ( with motion acceleration noise)**

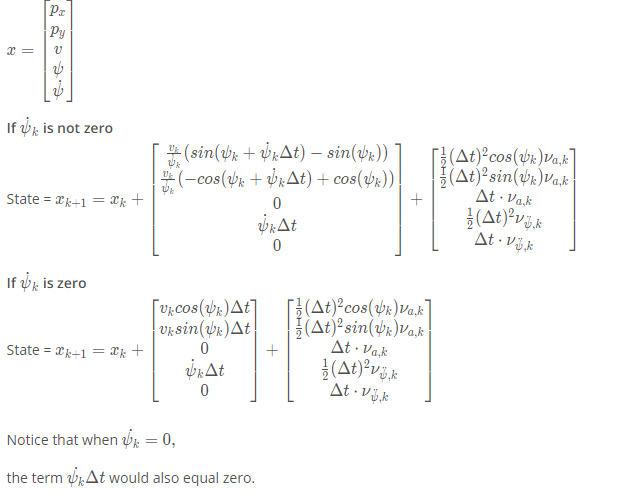
 



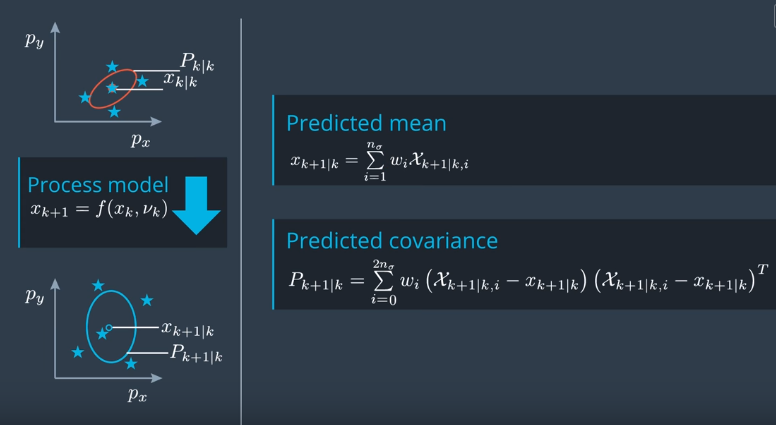
**7.19 Sigma point prediction**

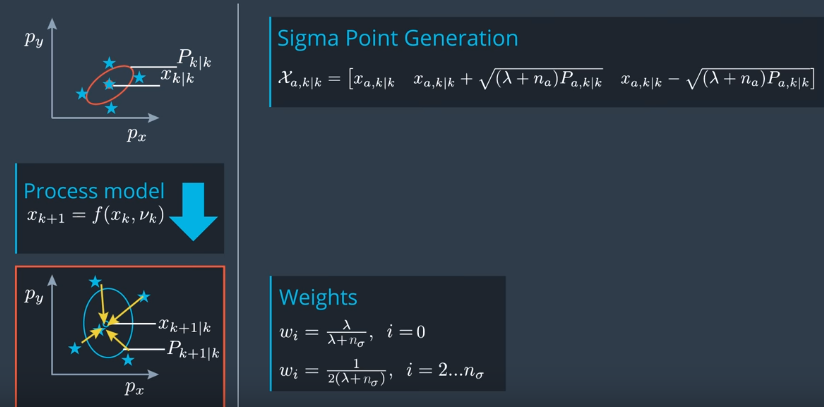


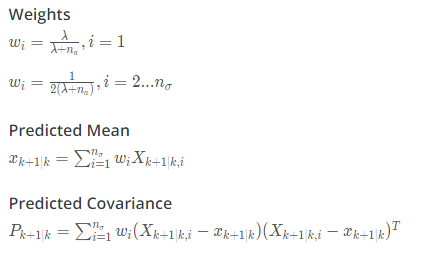




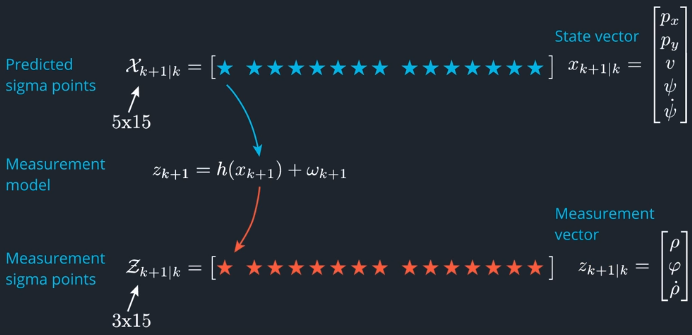
**7.22 Predict mean and covariance**

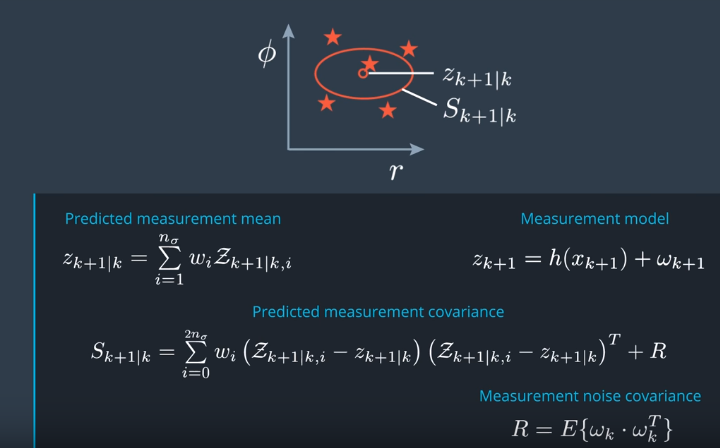


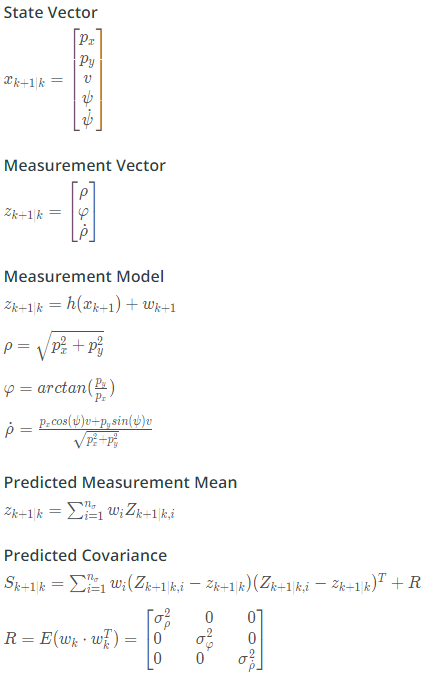


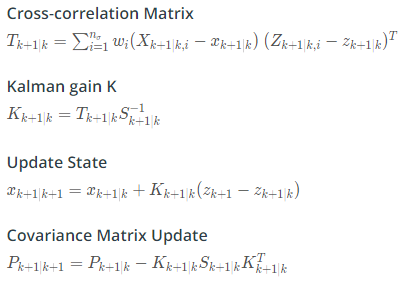


**7.25 Update : Measurement prediction ( Radar ?)**









**7.31 Noise evaluation for all Bayesian filter**

