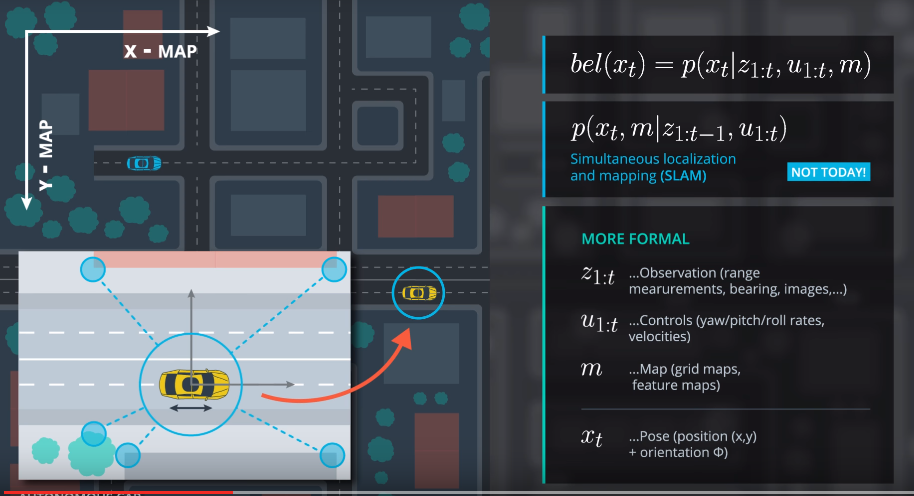
Markov Localization

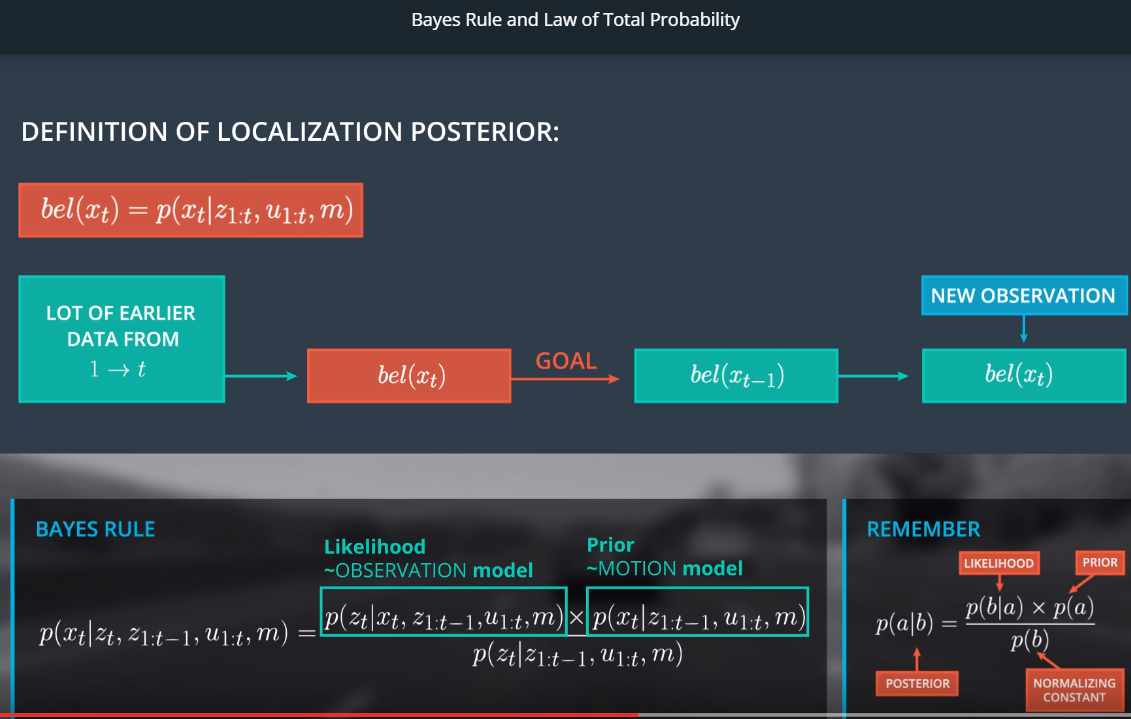
11.2 localization Posterior

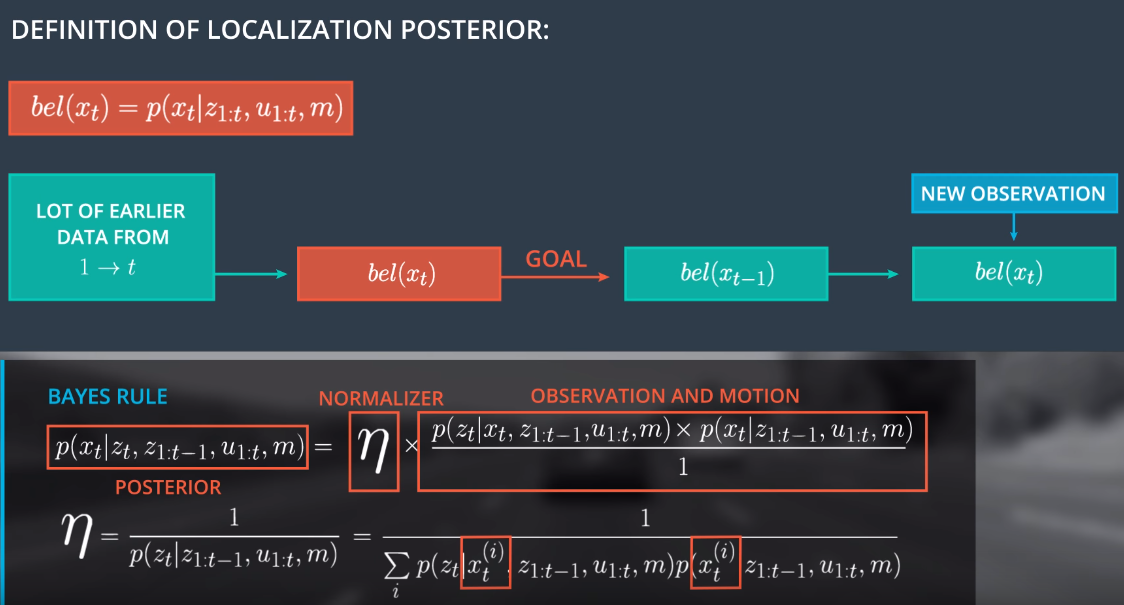


Simultaneous localization and mapping ( SLAM)

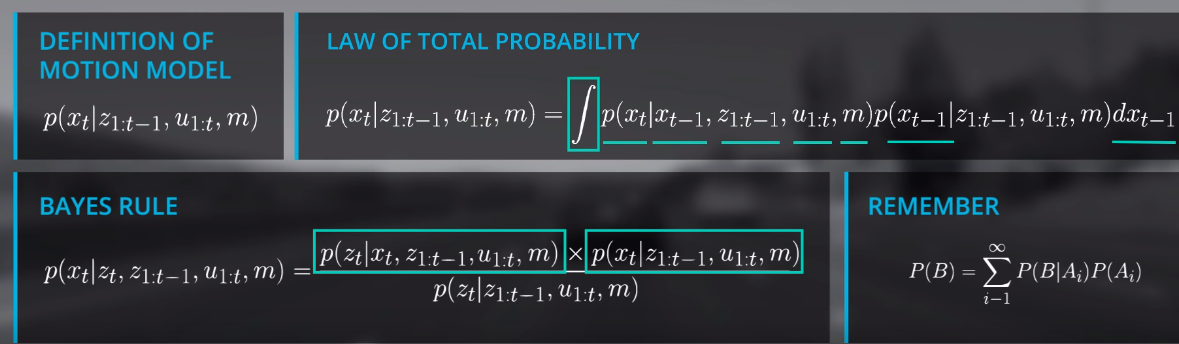


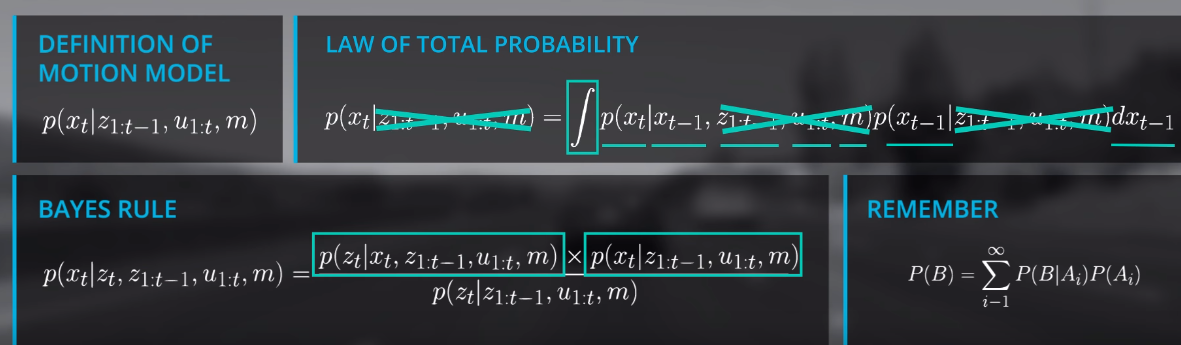
11.9 Bayes Rule and law of total Probability

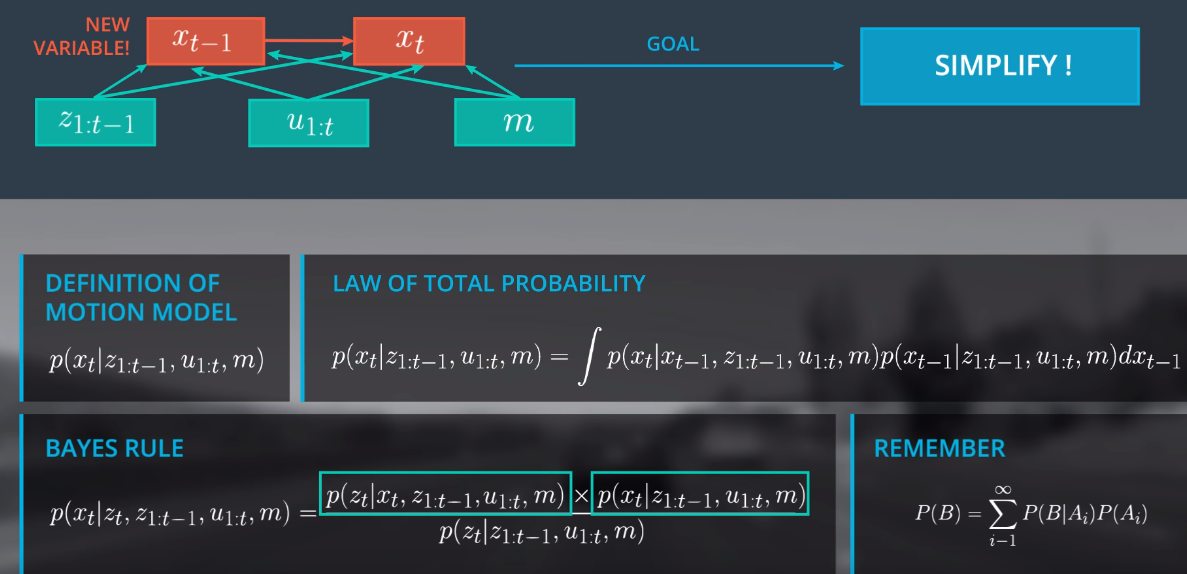




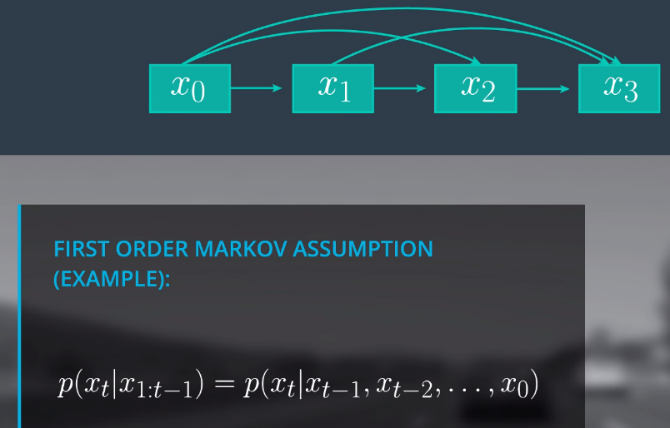
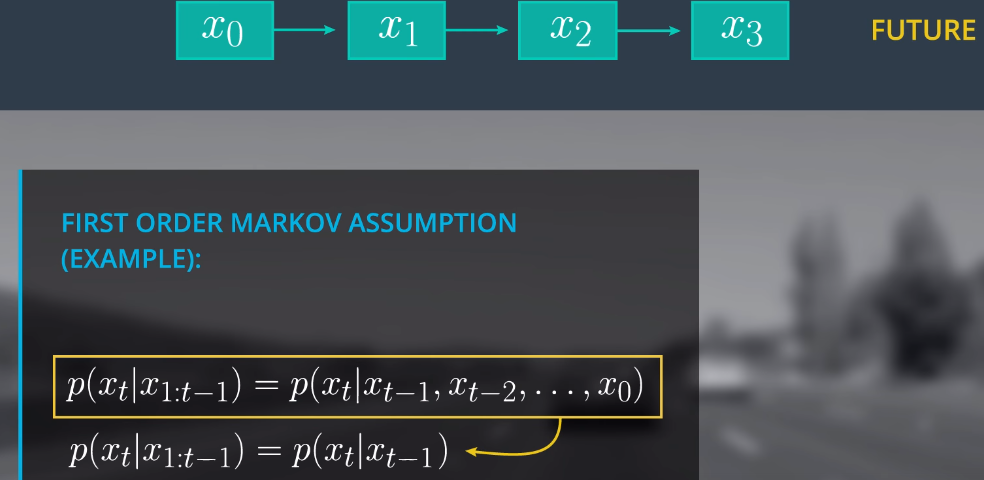
11.11



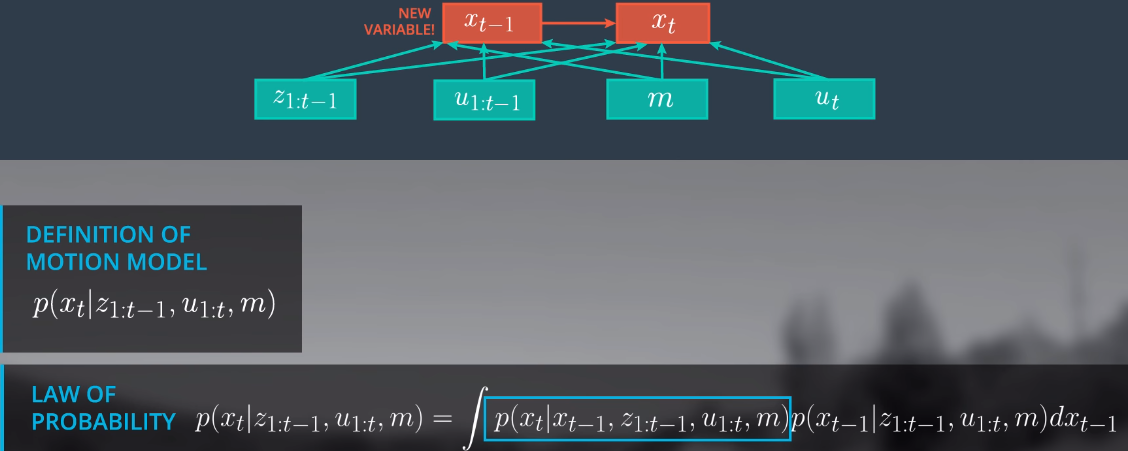


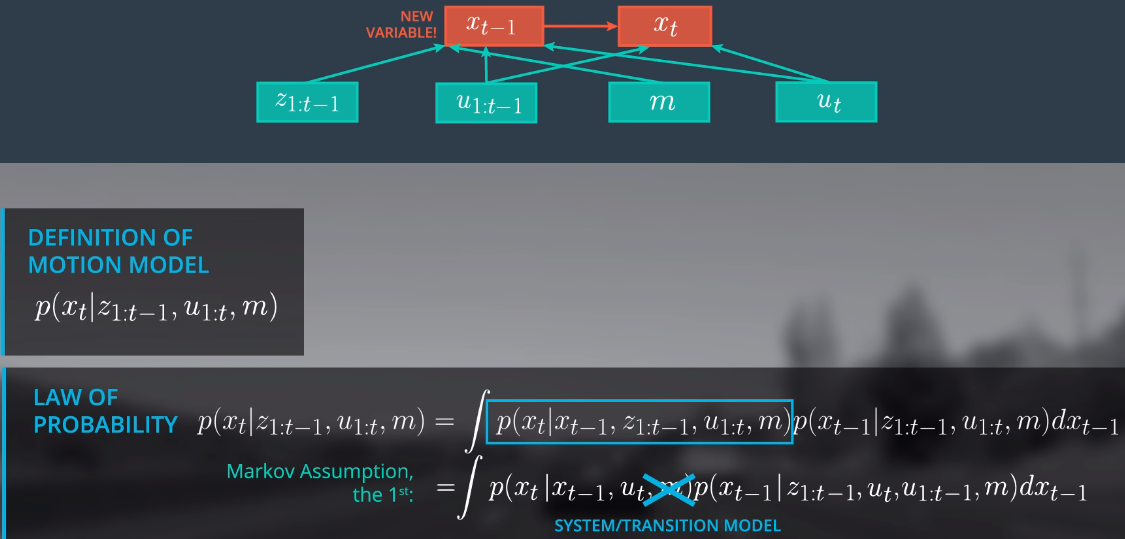


11.13 Markov Assumption for Motion Model

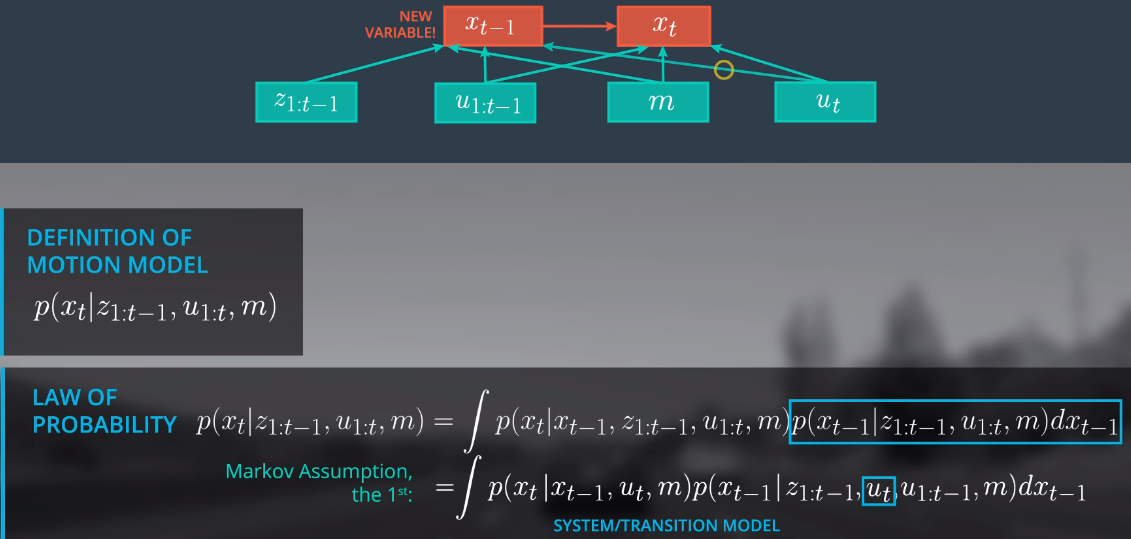


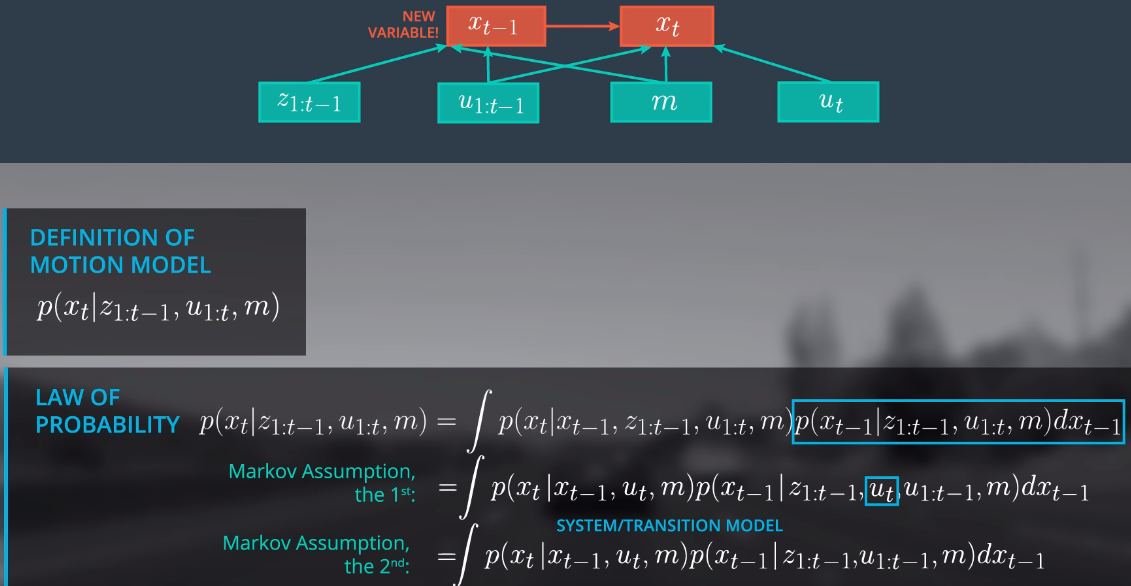
1st Assumption,



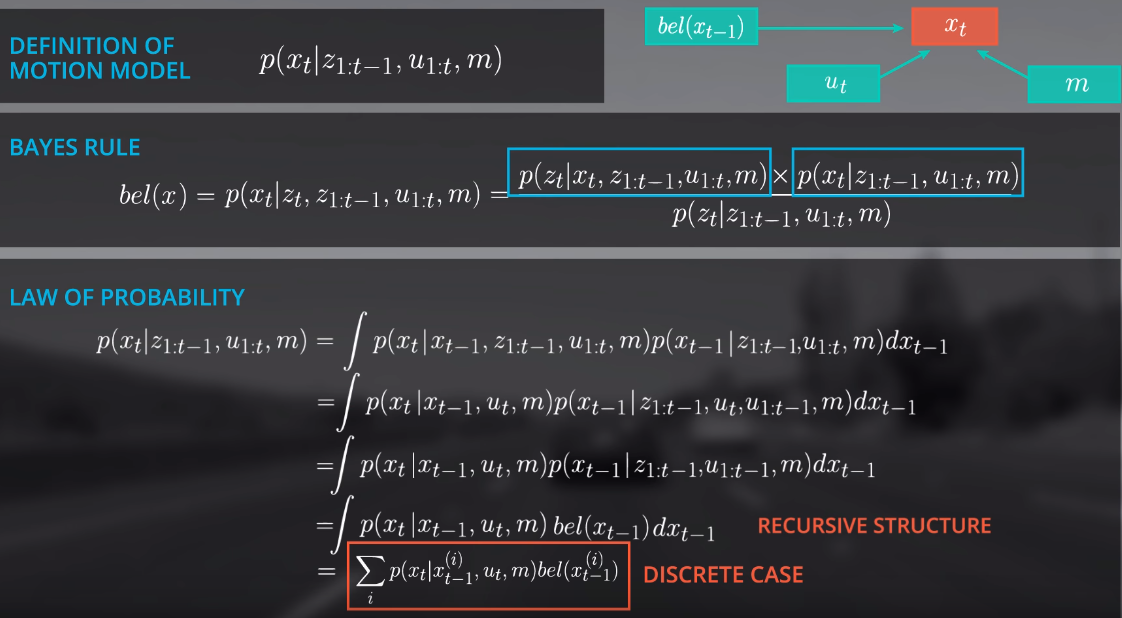


2nd Assumption





11.15 Recursive Structure



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

11.16 implement Motion Model

