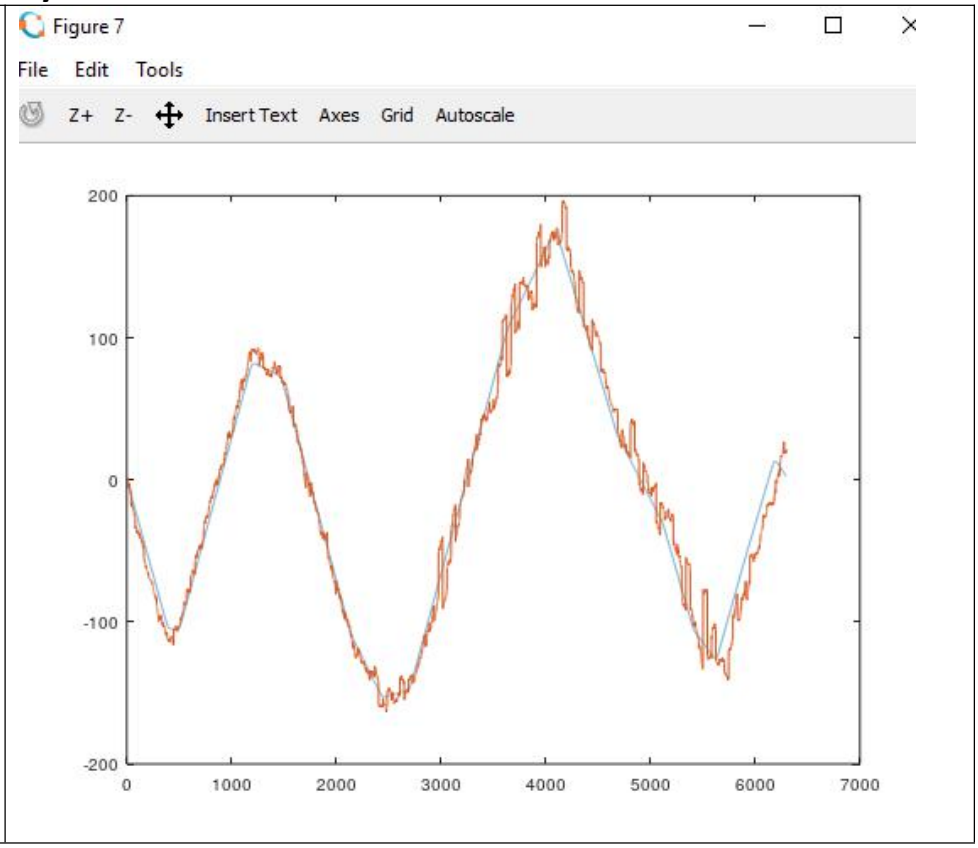
Experiment with PCBC for analysis:

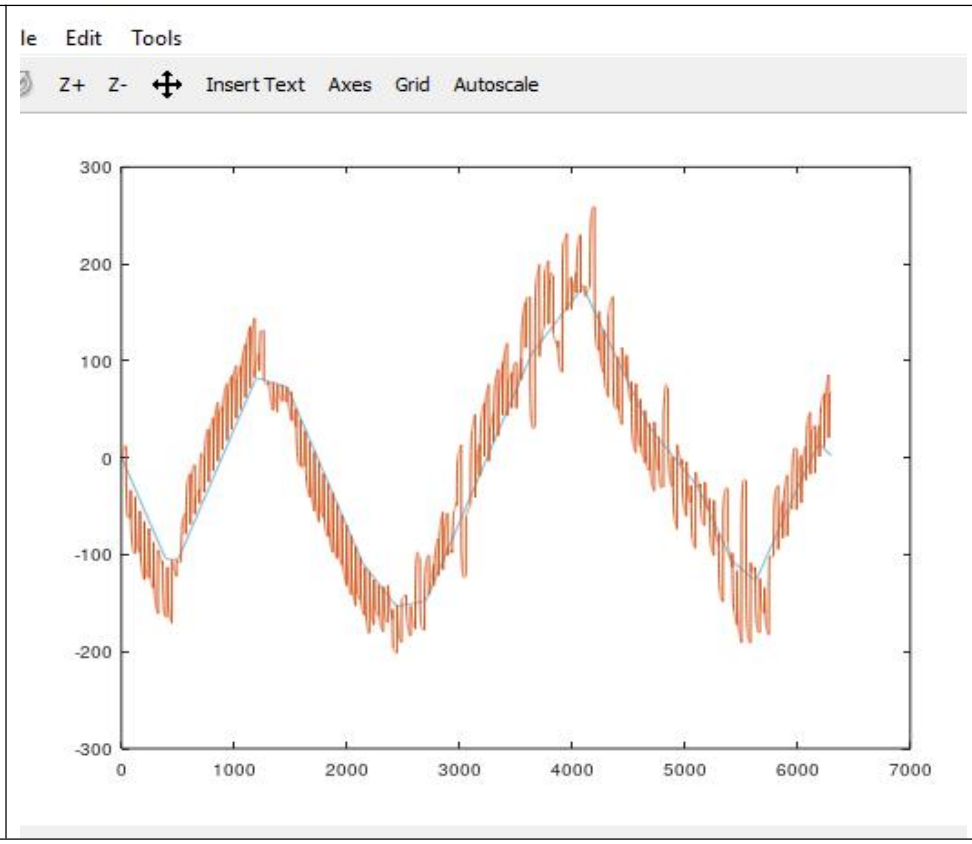
Iteration=5
AIMU = 0.1
ADVL = 0.01
AUSBL=40

SigmaIMU=1
SigmaDVL = 20
SigmaUSBL = 0.1

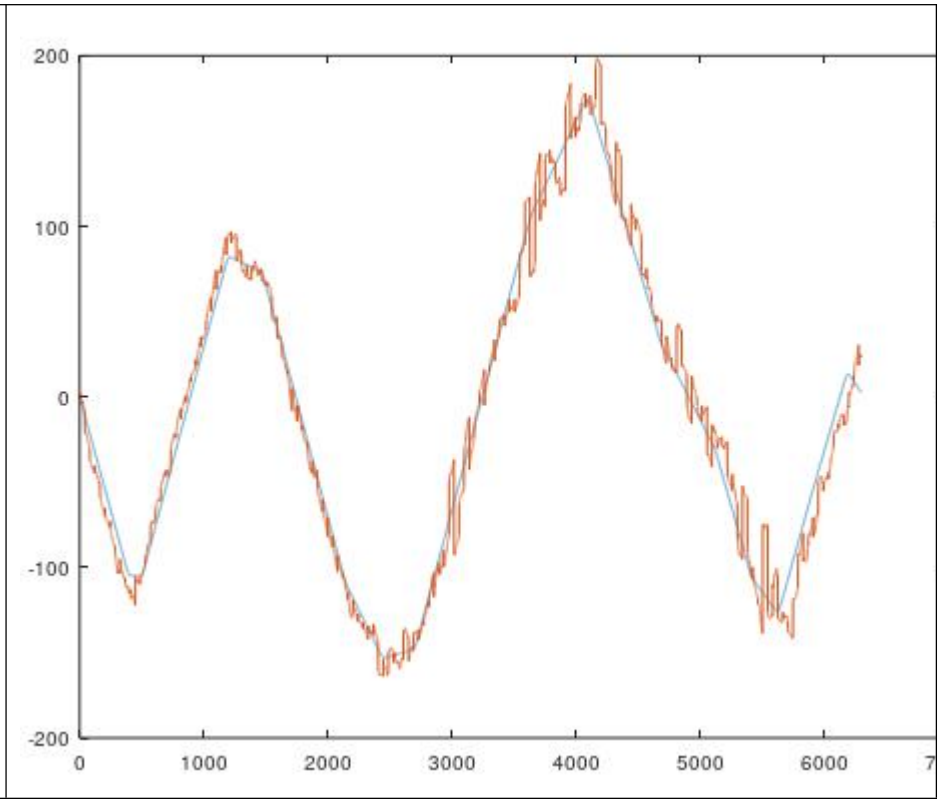


Iteration = 1
AIMU = 0.1
ADVL = 0.01
AUSBL=40

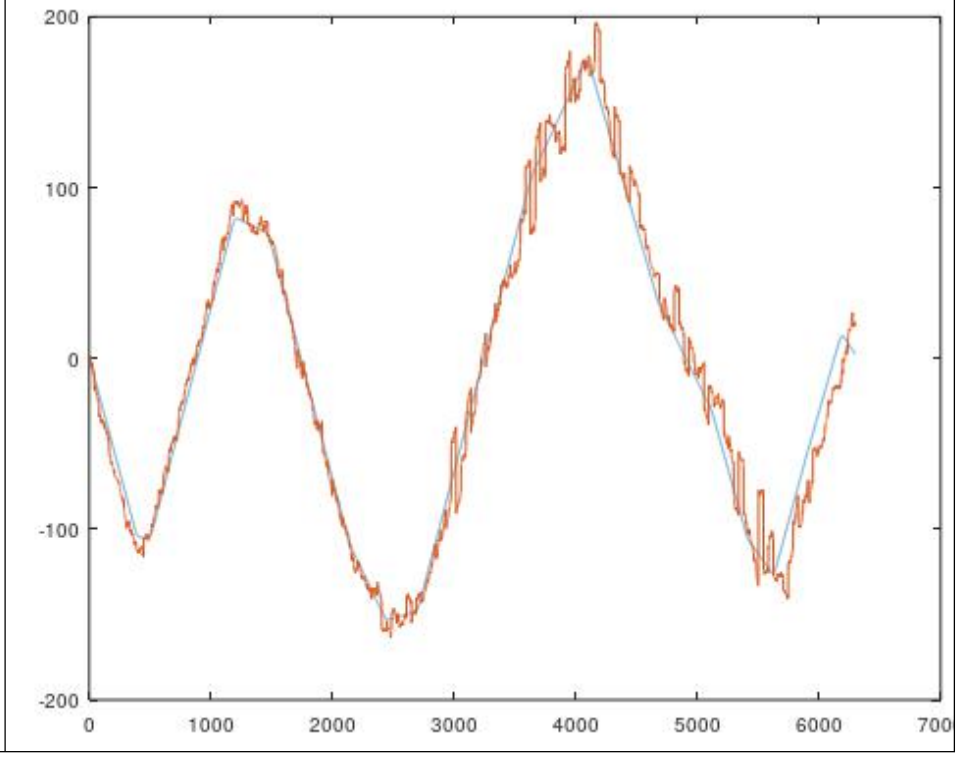
SigmaIMU=1
SigmaDVL = 20
SigmaUSBL = 0.1

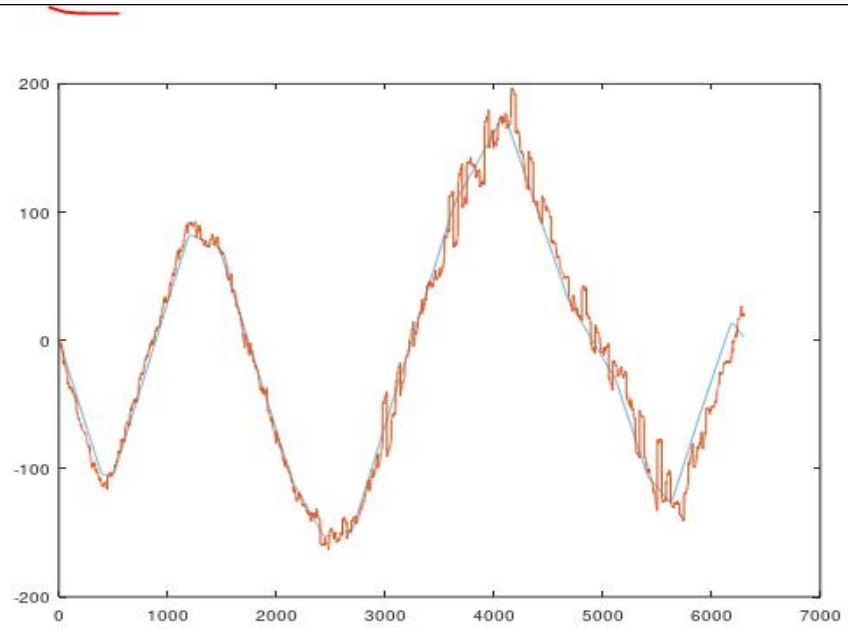


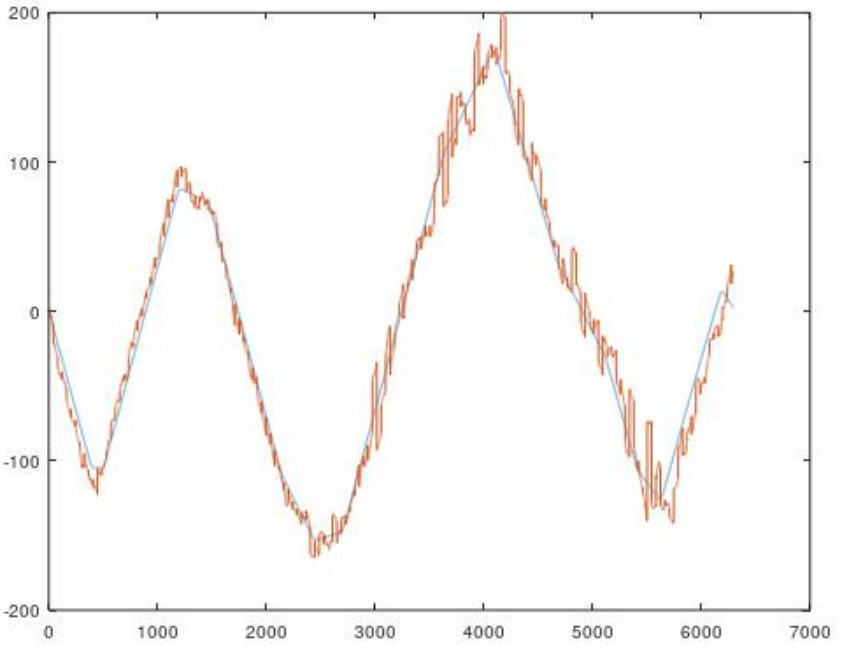
iter=5;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=1;
ADVL=0.01;
sigmaDVL=20;
AUSBL=40;
sigmaUSBL=0.1;



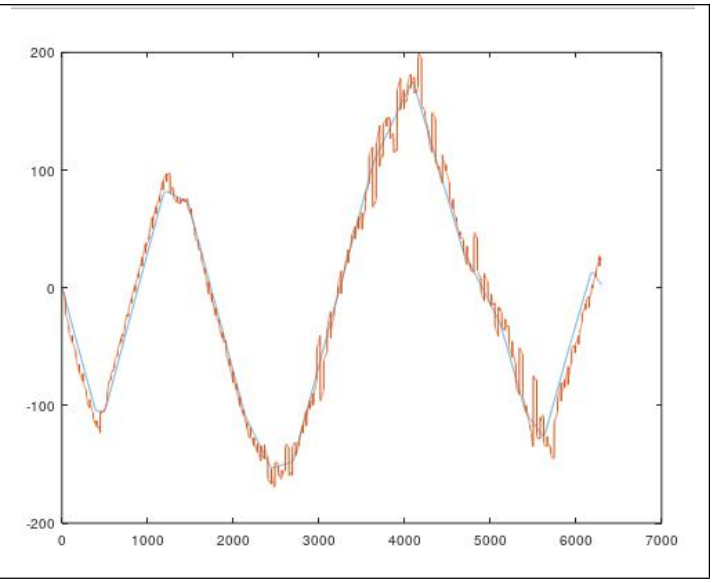
iter=25;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=1;
ADVL=0.01;
sigmaDVL=20;
AUSBL=40;
sigmaUSBL=0.1;



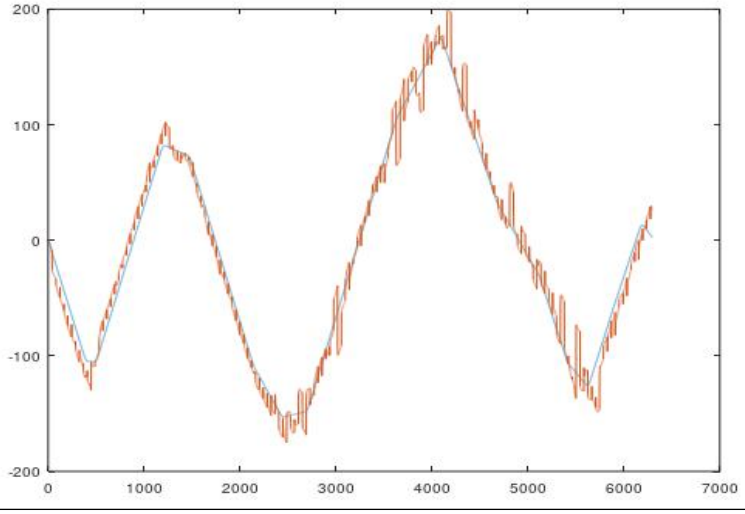
iter=5;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=1;
ADVL=0.1;
sigmaDVL=20;
AUSBL=40;
sigmaUSBL=0.1;
	

iter=5;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=1;
ADVL=0.01;
sigmaDVL=30;
AUSBL=40;
sigmaUSBL=0.1;
	

iter=10;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=0.1;
ADVL=0.01;
sigmaDVL=20;
AUSBL=40;
sigmaUSBL=0.1;

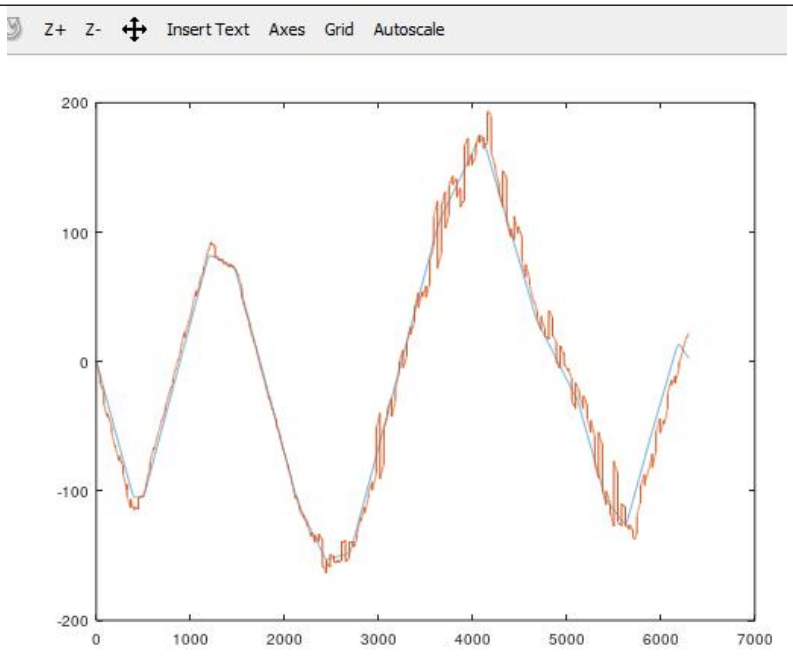


iter=10;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=0.2;
ADVL=0.1;
sigmaDVL=20;
AUSBL=40;
sigmaUSBL=0.1;

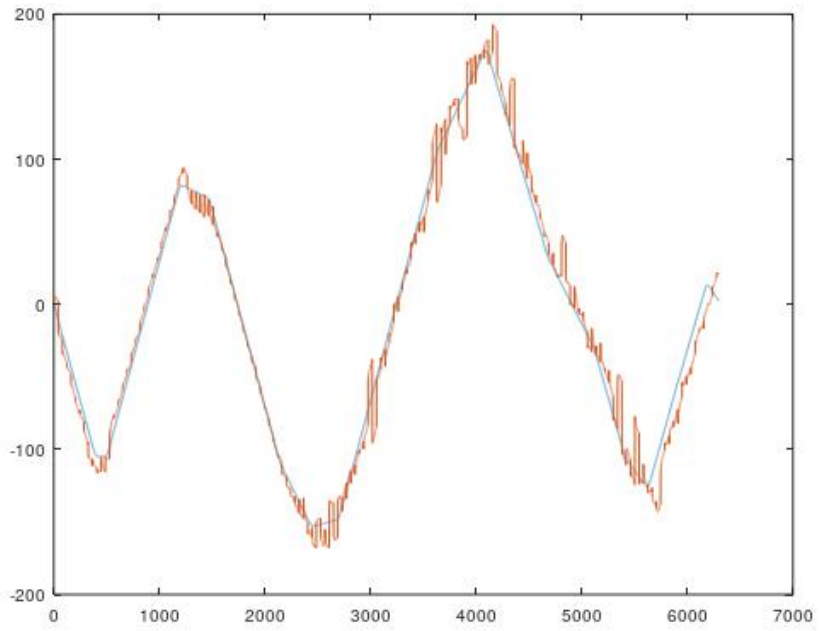


iter=10;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=20;
ADVL=0.1;
sigmaDVL=0.2;
AUSBL=40;
sigmaUSBL=0.1;

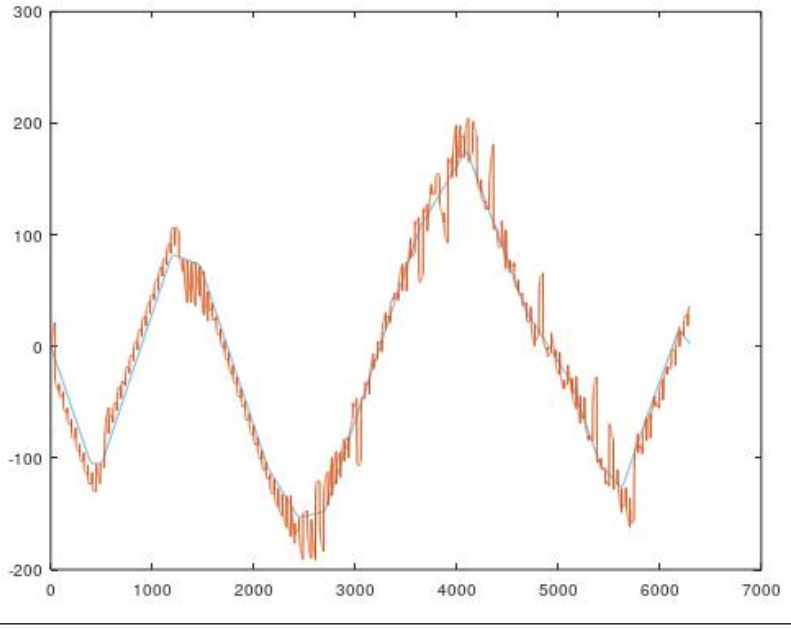
*see IMU smooth behavior mA



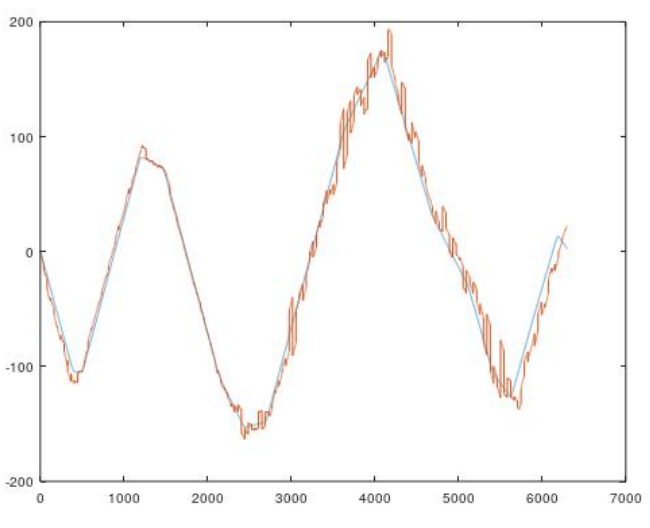
iter=10;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=20;
ADVL=0.1;
sigmaDVL=10;
AUSBL=40;
sigmaUSBL=0.1;



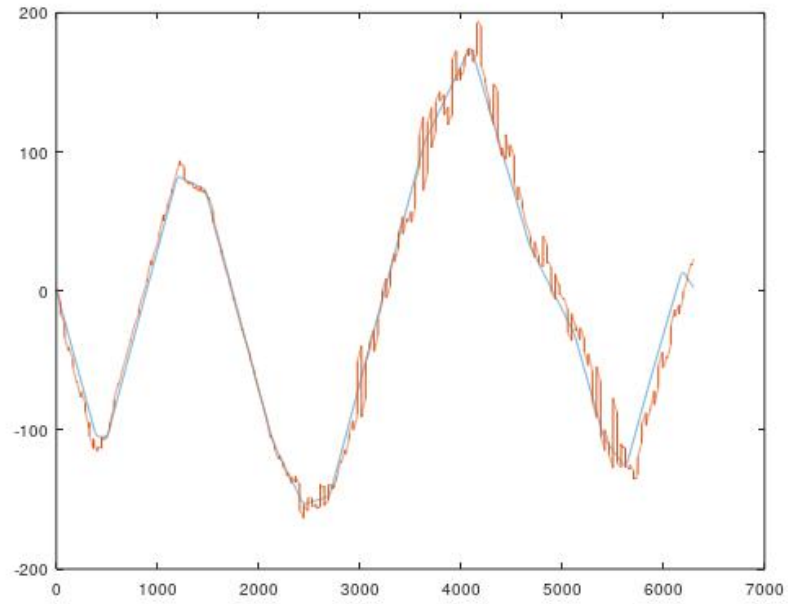
iter=10;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=20;
ADVL=0.1;
sigmaDVL=20;
AUSBL=40;
sigmaUSBL=0.1;

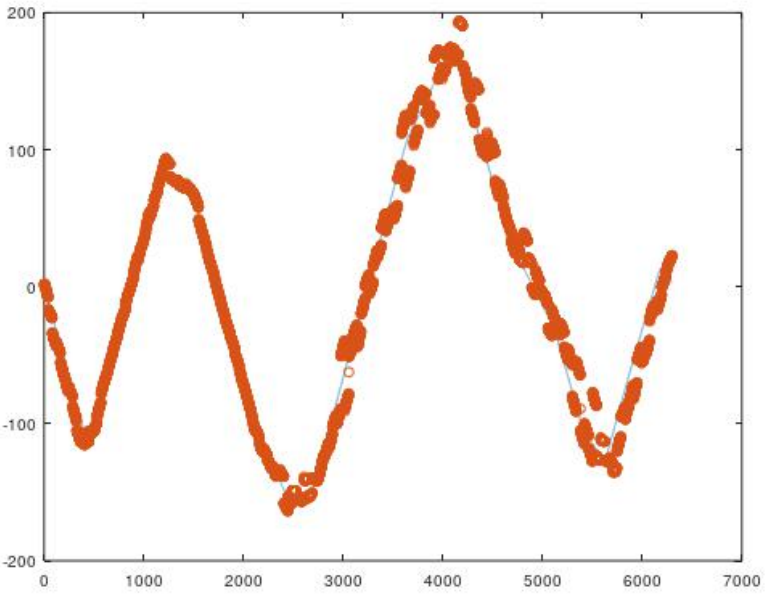


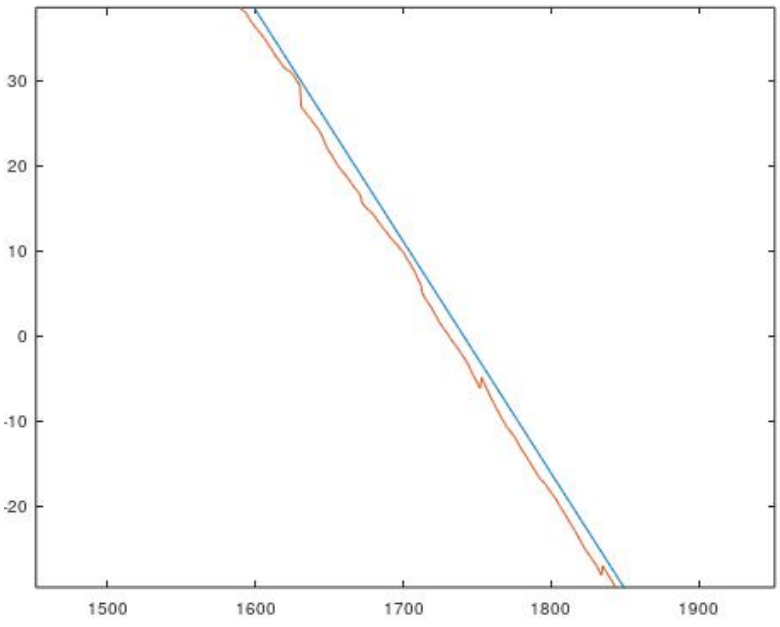
iter=10;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=30;
ADVL=0.1;
sigmaDVL=0.2;
AUSBL=40;
sigmaUSBL=0.1;



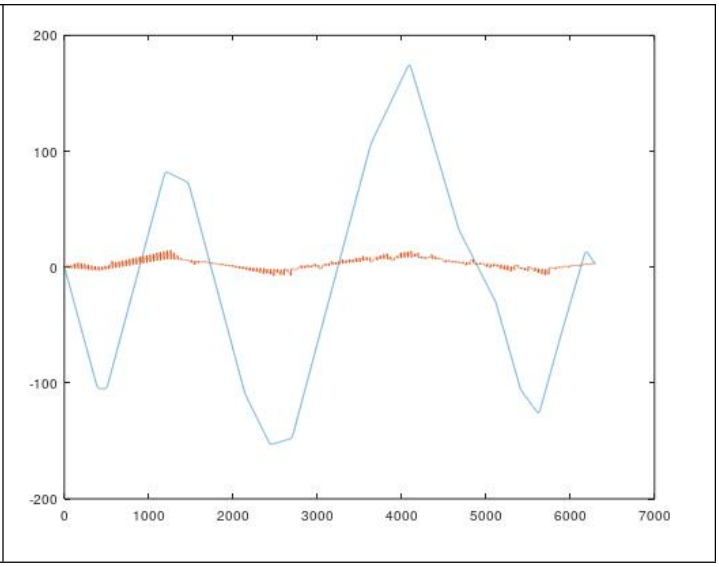
iter=10;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=30;
ADVL=0.1;
sigmaDVL=2;
AUSBL=40;
sigmaUSBL=0.1;



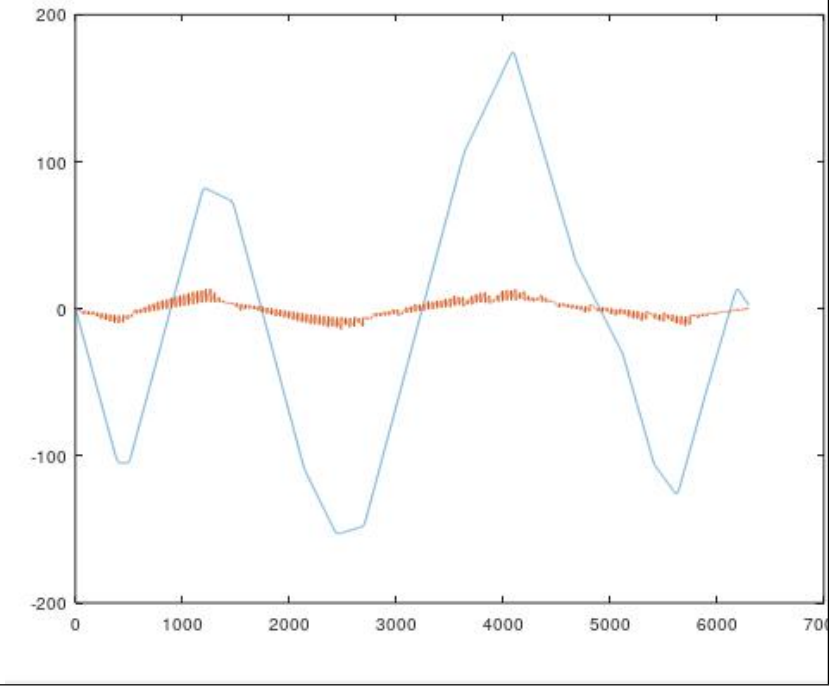




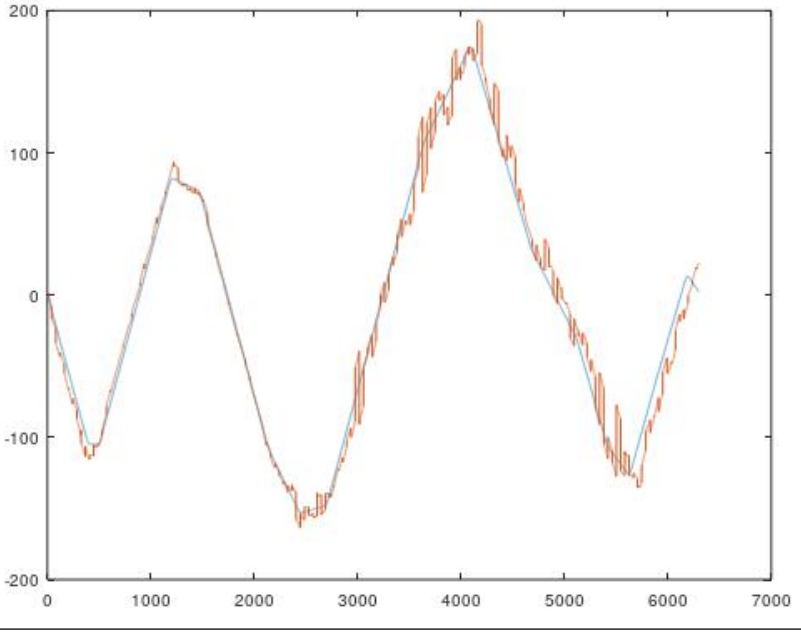
iter=10;
#setting Input for inertial sensor and positioning
AIMU=1;
sigmaIMU=30;
ADVL=1;
sigmaDVL=20;
AUSBL=1;
sigmaUSBL=0.1;



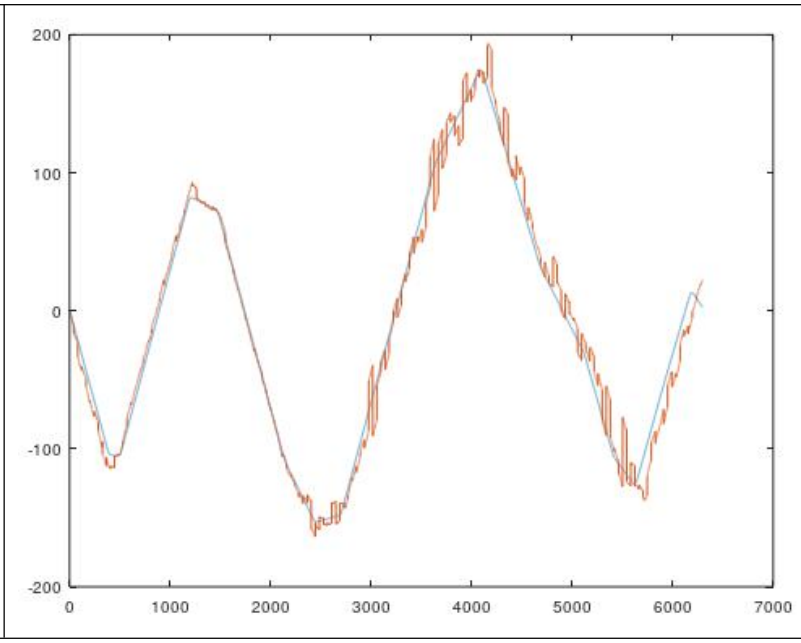
iter=10;
#setting Input for inertial sensor and positioning
AIMU=1;
sigmaIMU=30;
ADVL=1;
sigmaDVL=2;
AUSBL=1;
sigmaUSBL=0.1;



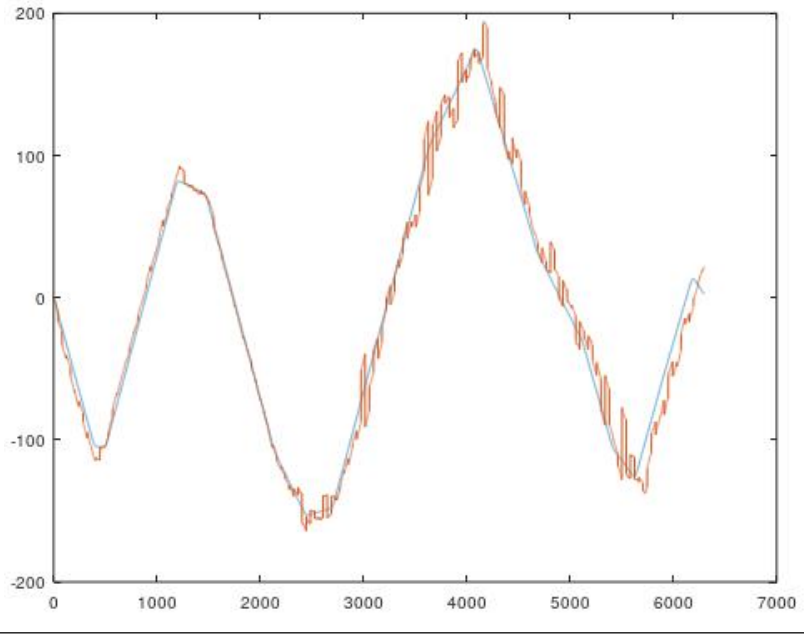
iter=10;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=30;
ADVL=0.1;
sigmaDVL=2;
AUSBL=40;
sigmaUSBL=0.1;



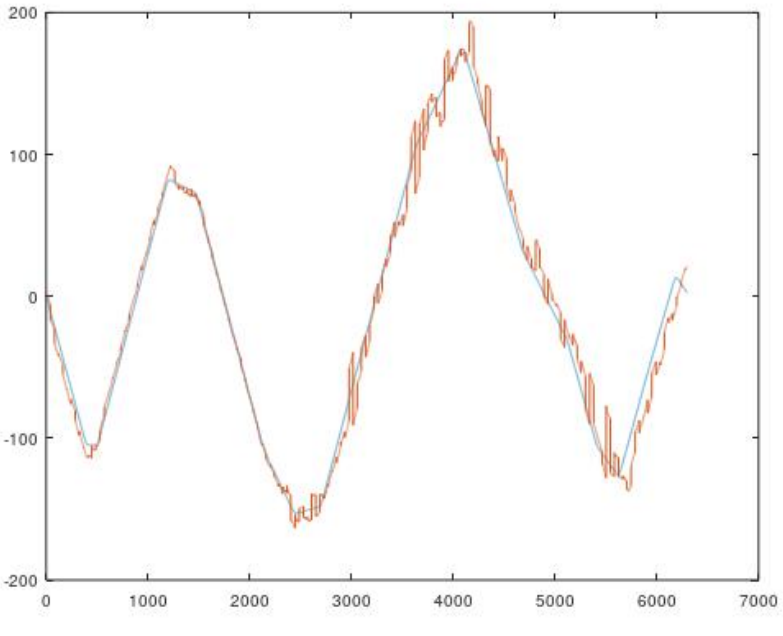
iter=50;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=30;
ADVL=0.1;
sigmaDVL=2;
AUSBL=40;
sigmaUSBL=0.1;



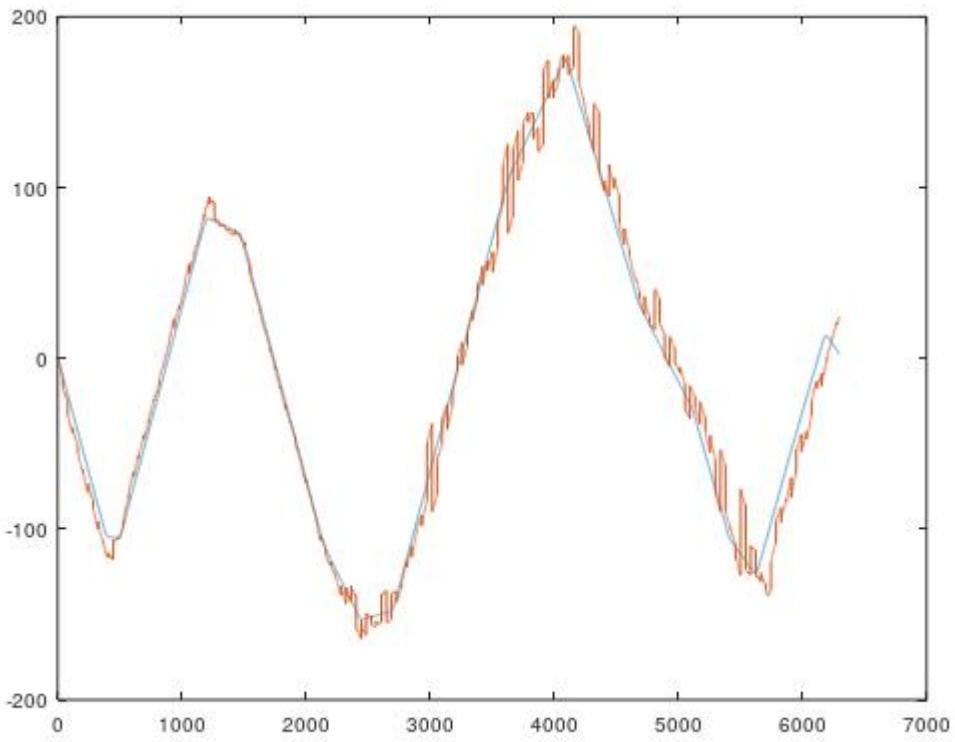
iter=50;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=20;
ADVL=0.1;
sigmaDVL=5;
AUSBL=40;
sigmaUSBL=0.1;

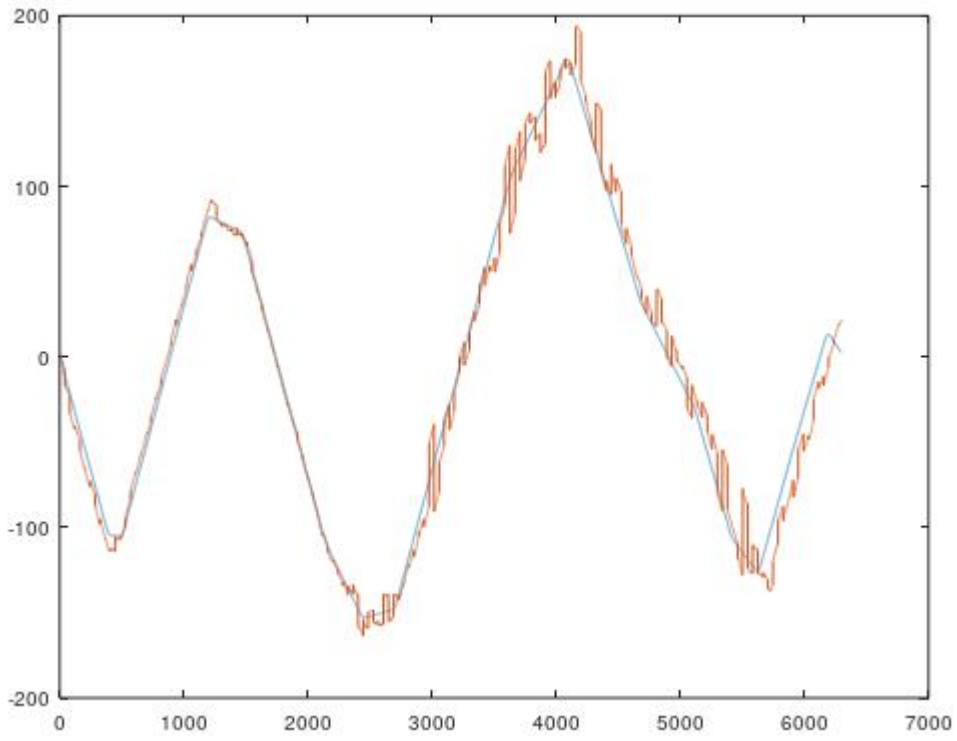


iter=50;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=20;
ADVL=0.1;
sigmaDVL=10;
AUSBL=40;
sigmaUSBL=0.1;

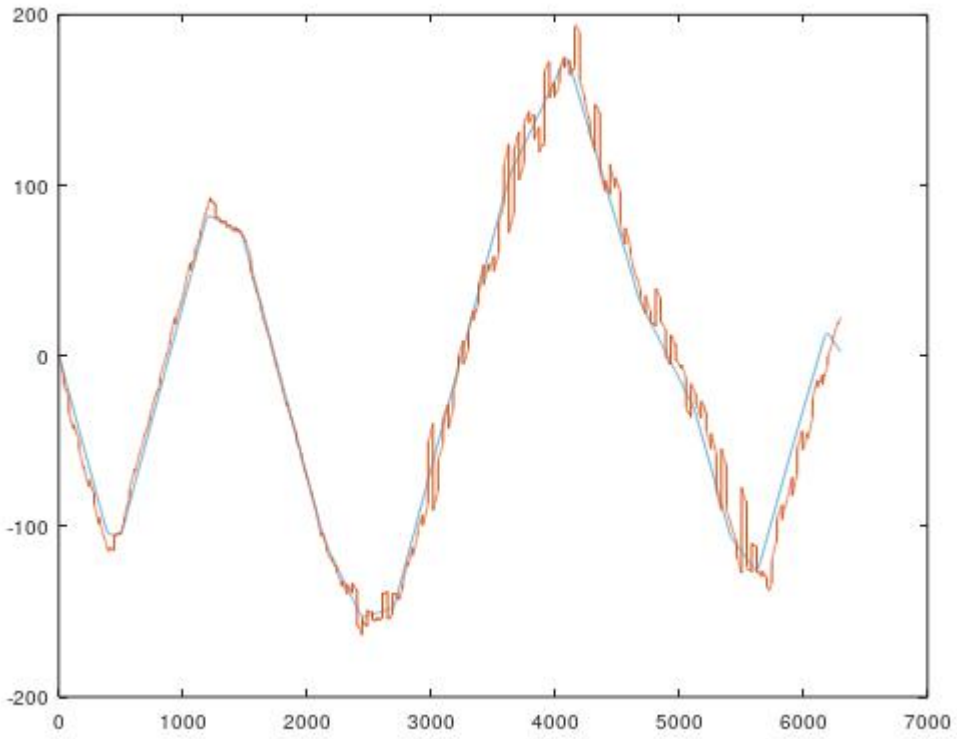


Now with usbl

iter=50;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=20;
ADVL=0.1;
sigmaDVL=10;
AUSBL=40;
sigmaUSBL=5;
	

iter=50;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=20;
ADVL=0.1;
sigmaDVL=10;
AUSBL=40;
sigmaUSBL=0.2;
	

iter=40;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=20;
ADVL=0.1;
sigmaDVL=1;
AUSBL=40;
sigmaUSBL=0.2;



Usbl 100 itr

iter=40;
#setting Input for inertial sensor and positioning
AIMU=0.1;
sigmaIMU=20;
ADVL=0.1;
sigmaDVL=2;
AUSBL=40;
sigmaUSBL=0.2;