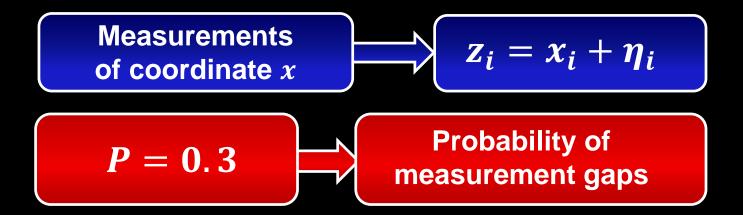
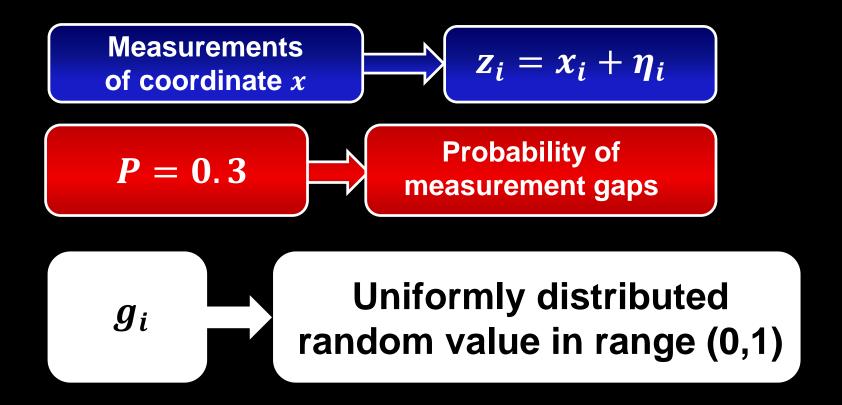


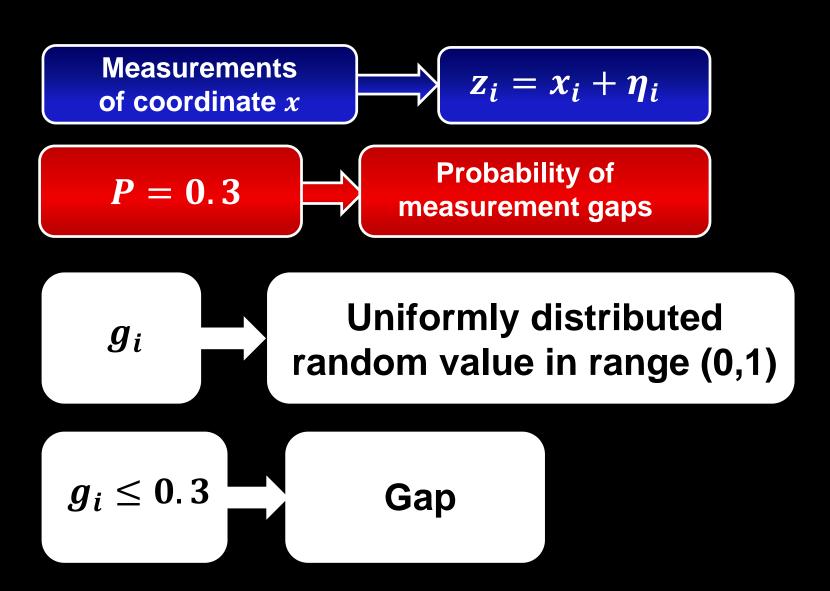
#### "Space Data Processing: Making Sense of Experimental Data"

Laboratory work 8
Tracking and forecasting
in conditions of measurement gap

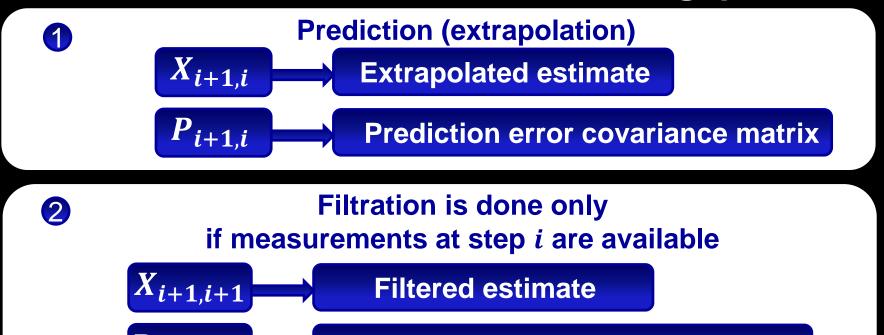
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Filtration error covariance matrix

Prediction (extrapolation)  $X_{i+1,i}$ Extrapolated estimate  $P_{i+1,i}$ Prediction error covariance matrix

**2** Filtration is done only if measurements at step i are available

$$X_{i+1,i+1}$$
 Filtered estimate

 $P_{i+1,i+1}$  Filtration error covariance matrix

If measurements at step i are not available, then filtered estimate is equal to extrapolated estimate

$$X_{i+1,i+1} = X_{i+1,i}$$
 $P_{i+1,i+1} = P_{i+1,i}$