

Derivation of process covariance matrix Q for the EKF with UKV motion model.

$$\text{noise} = \begin{pmatrix} a_a \\ a_{\ddot{\psi}} \end{pmatrix}$$

$$\rceil = \begin{pmatrix} \frac{1}{2}(\Delta t)^2 \cos(\psi) a_a \\ \frac{1}{2}(\Delta t)^2 \sin(\psi) a_a \\ \Delta t a_a \\ \frac{1}{2}(\Delta t)^2 a_{\ddot{\psi}} \\ \Delta t a_{\ddot{\psi}} \end{pmatrix}$$

$$\rceil = G a$$

$$G = \begin{pmatrix} \frac{1}{2}(\Delta t)^2 \cos(\psi) & 0 \\ \frac{1}{2}(\Delta t)^2 \sin(\psi) & 0 \\ \Delta t & 0 \\ 0 & \frac{1}{2}(\Delta t)^2 \\ 0 & \Delta t \end{pmatrix}$$

$$Q = E[\mathbf{G} \mathbf{a} \mathbf{a}^T \mathbf{G}^T] = \mathbf{G} E[\mathbf{a} \mathbf{a}^T] \mathbf{G}^T$$

$$E[\mathbf{a} \mathbf{a}^T] = \begin{pmatrix} \sigma_{aa}^2 & 0 \\ 0 & \sigma_{aj}^2 \end{pmatrix}$$

$$\mathbf{G}^T = \begin{pmatrix} \frac{1}{2}(At)^2 \cos \psi & \frac{1}{2}(At)^2 \sin \psi & At & 0 & 0 \\ 0 & 0 & 0 & \frac{1}{2}(At)^2 & At \end{pmatrix}$$

$$Q = \begin{pmatrix} \frac{1}{2}(At)^2 \cos \psi & 0 \\ \frac{1}{2}(At)^2 \sin \psi & 0 \\ At & 0 \\ 0 & \frac{1}{2}(At)^2 \\ 0 & At \end{pmatrix} \begin{pmatrix} \frac{1}{2}(At)^2 \cos \psi \sigma_{aa}^2 & \frac{1}{2}(At)^2 \sin \psi \sigma_{aa}^2 & At \sigma_{aa}^2 & 0 & 0 \\ 0 & 0 & 0 & \frac{1}{2} At^2 \sigma_{aj}^2 & At \sigma_{aj}^2 \end{pmatrix}$$

$$= \begin{pmatrix} \frac{1}{4}(At)^4 \cos^2 \psi \sigma_{aa}^2 & \frac{1}{4}(At)^4 \cos \psi \sin \psi \sigma_{aa}^2 & \frac{1}{2}(At)^3 \cos \psi \sigma_{aa}^2 & 0 & 0 \\ \frac{1}{4}(At)^4 \sin \psi \cos \psi \sigma_{aa}^2 & \frac{1}{4}(At)^4 \sin^2 \psi \sigma_{aa}^2 & \frac{1}{2}(At)^3 \sin \psi \sigma_{aa}^2 & 0 & 0 \\ \frac{1}{2}(At)^3 \cos \psi \sigma_{aa}^2 & \frac{1}{2}(At)^3 \sin \psi \sigma_{aa}^2 & At^2 \sigma_{aa}^2 & 0 & 0 \\ 0 & 0 & 0 & \frac{1}{4}(At)^4 \sigma_{aj}^2 & \frac{1}{2}(At)^3 \sigma_{aj}^2 \\ 0 & 0 & 0 & \frac{1}{2}(At)^3 \sigma_{aj}^2 & At^2 \sigma_{aj}^2 \end{pmatrix}$$