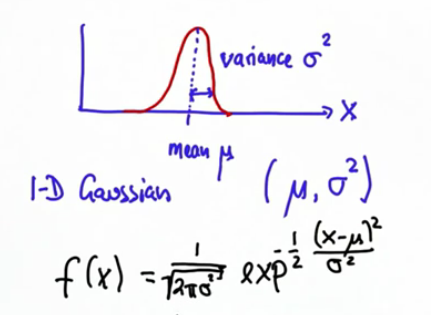
Tracking Filters:

     Continuous, Uni-modal: Kalman and Particle

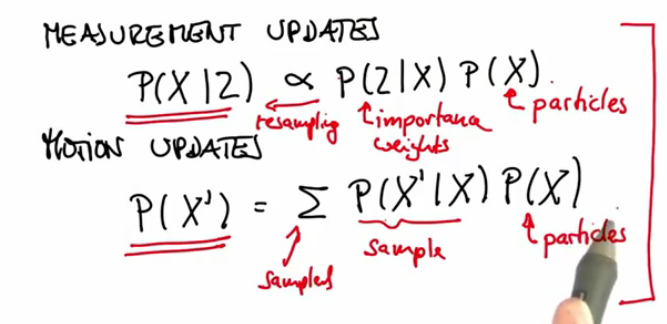
     Discrete, Muli-modal: Monte Carlo/Localization

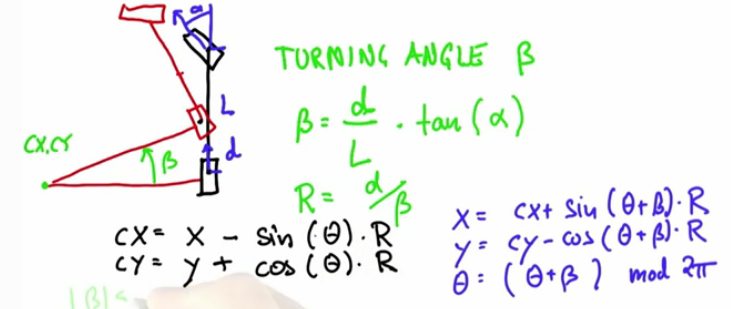


f(x) = .... \* exp(-.5 \* .... )

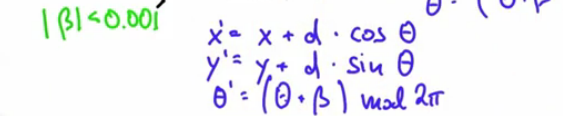
Update = Sense

Predict = Move



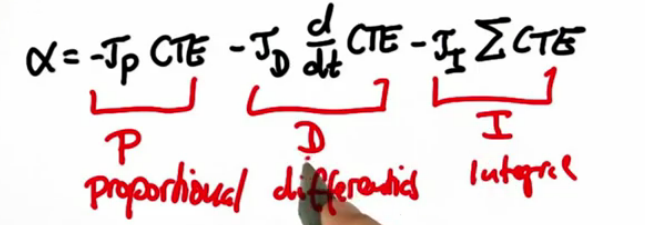


There are special rules with small Betas, to prevent division by zero:



Inline image 3

arctan2 gives the angular orientation to a position give a change in x/y



tau\_d is a "smoothing" term

