Trimmean()

Mad()

Plot of errors(mean variance) to #nodes actived in the last n seconds

Root mean square of derivation from the true trajectory of EKF

Calibration-Free Localization.m >>

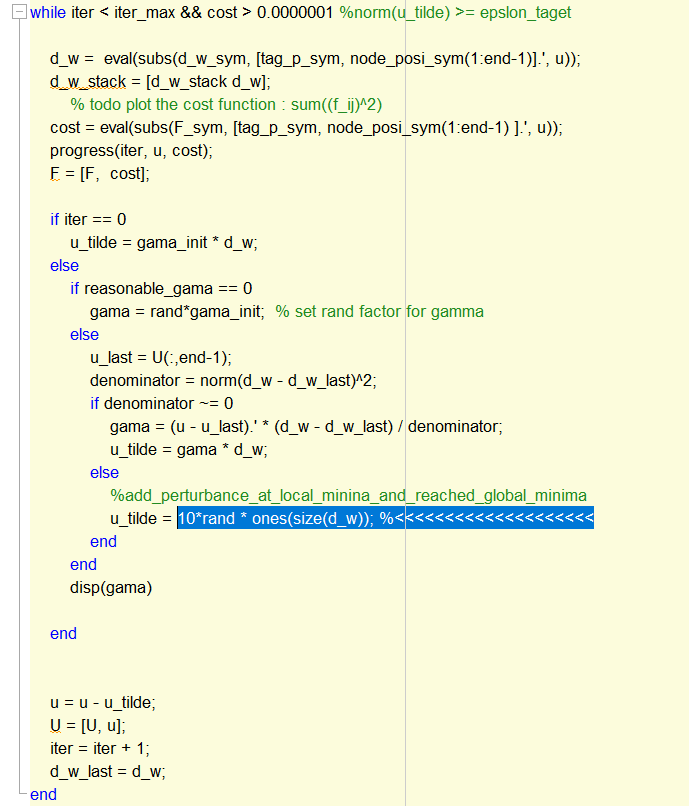
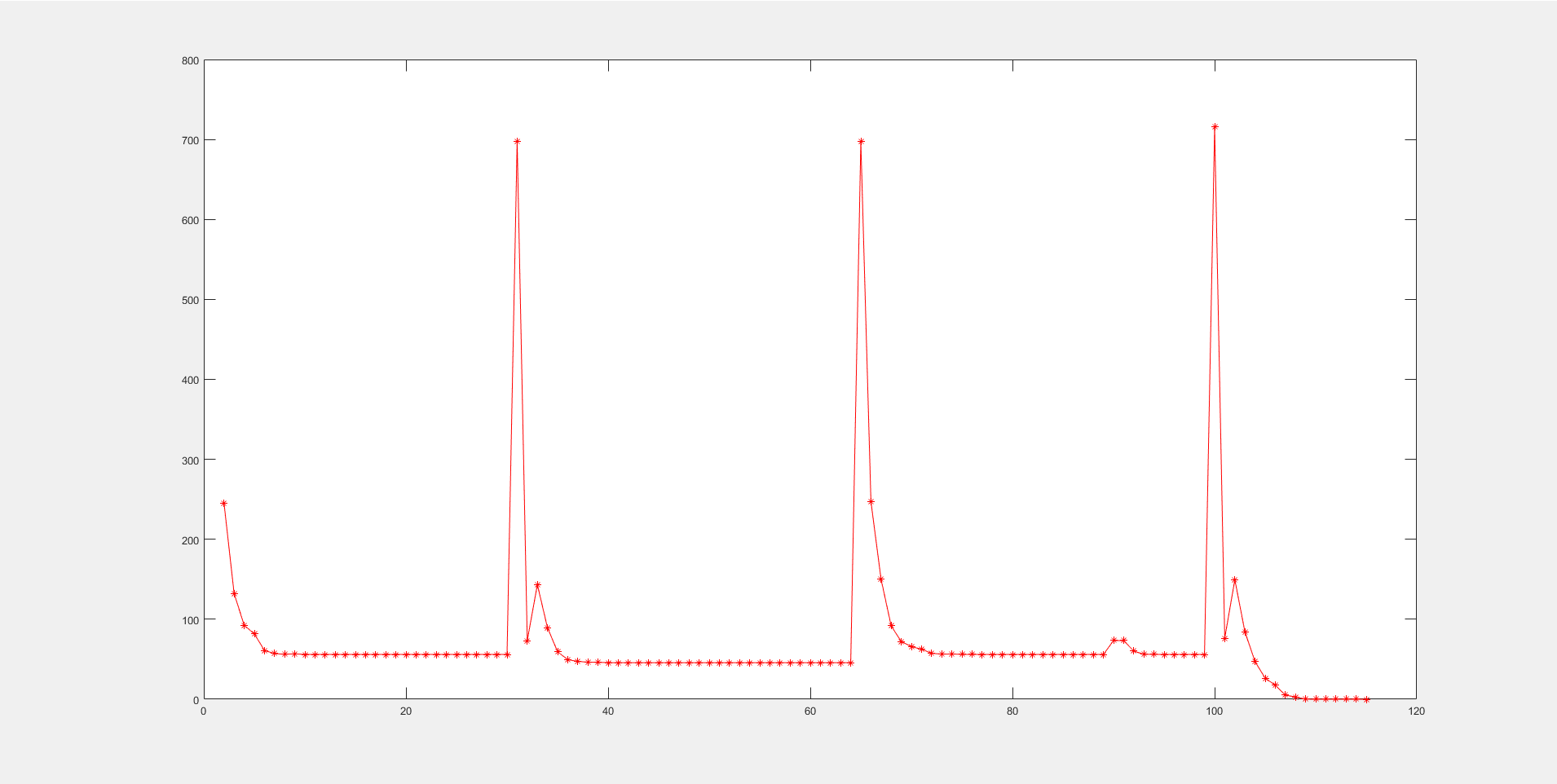
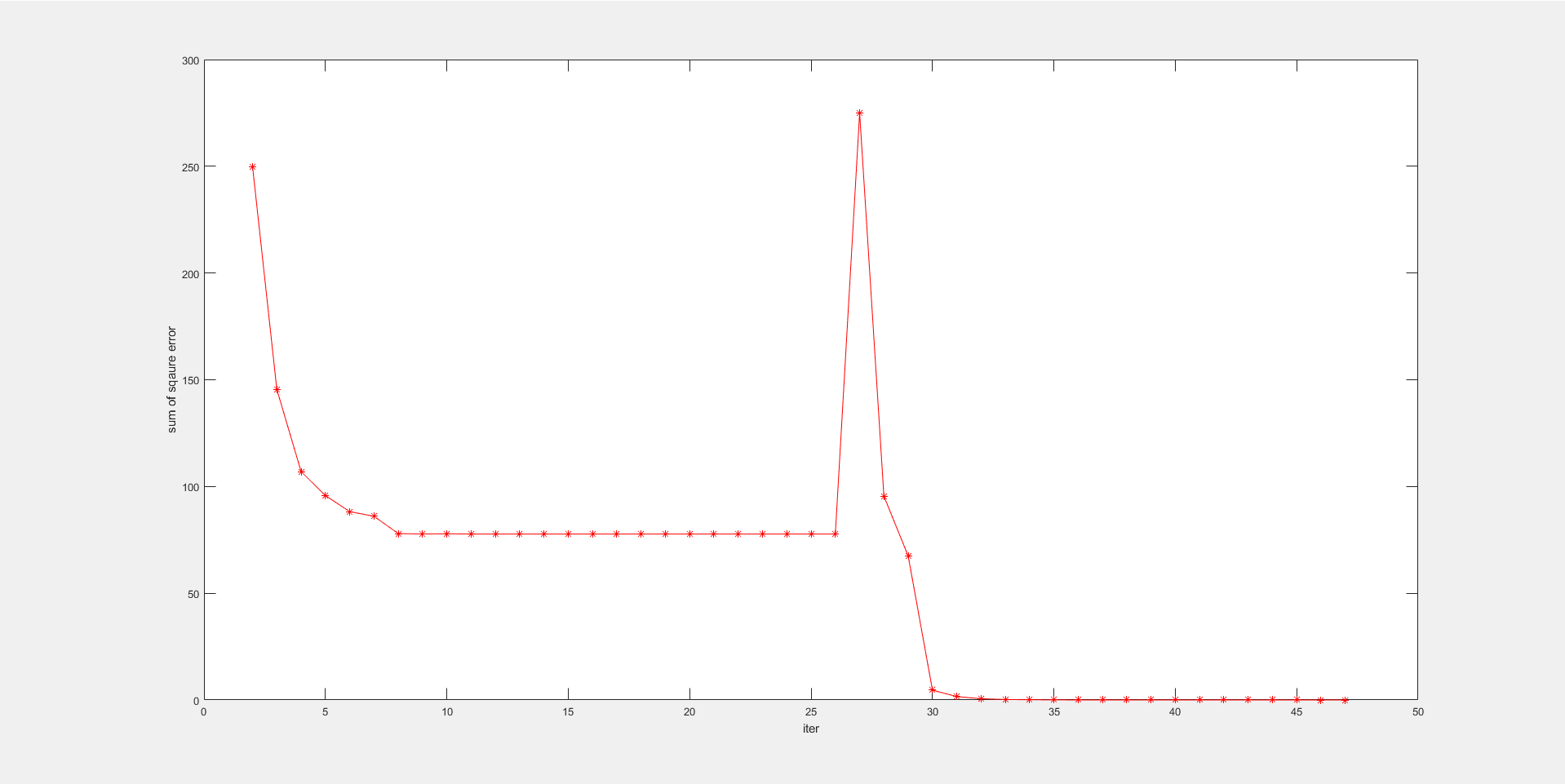
set rand factor for gamma seems could solve local minimal problem :D

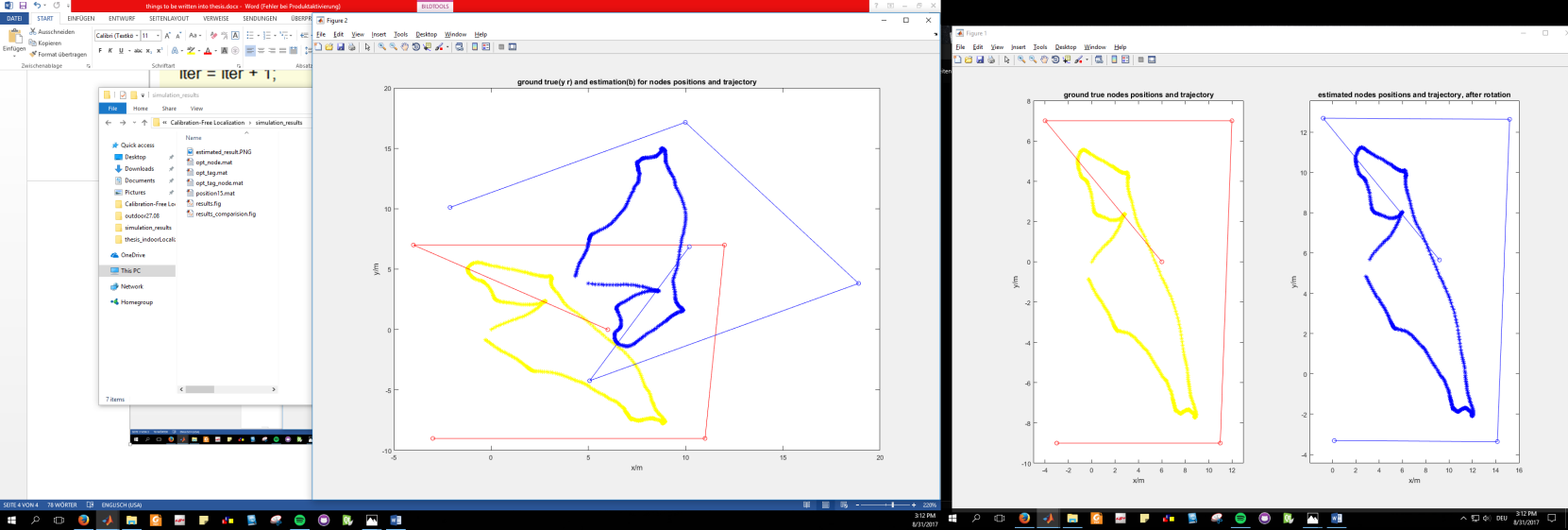
Histogram of outdoor measurements, fitting parameter, fitting results

0x1A1A is much better than others, statistics result to proof that. And that is why the wake up modul should be turn off to test the algorithm

Calibration-Free Localization

add\_perturbance\_at\_local\_minina\_and\_reached\_global\_minima



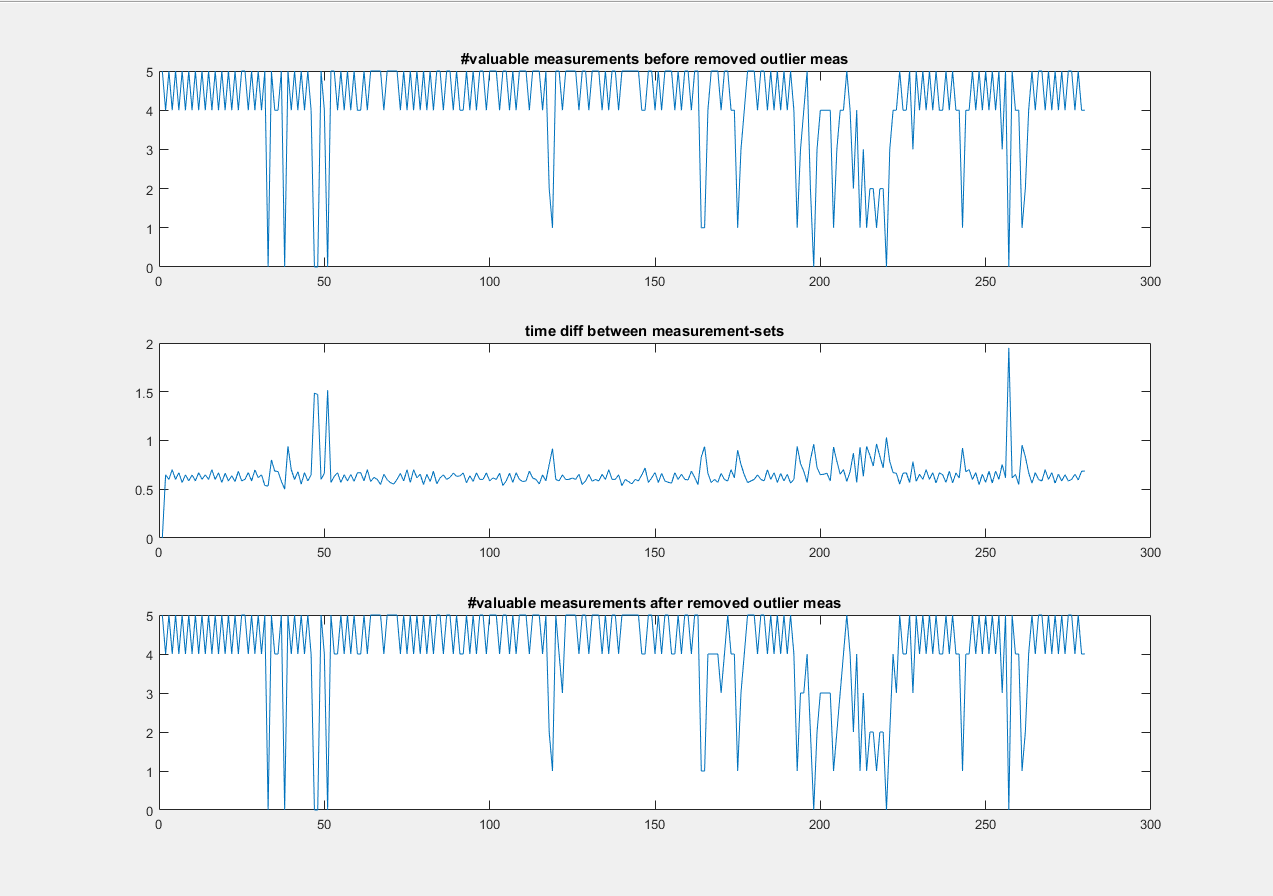


Kstest() matlab

Use hampel() in matlan to find out and remove outlier

Or ekf when time\_diff(i) is too big(>0.9), the estimation for i+1 has bigger Q and smaller R

# Rayleigh distribution



#valuable measurements before/ after removed outlier meas

time diff between measurement-sets

In experiment 4

Command in ‘KF\_using\_HTerm\_data.m’ , ‘title('#valuable measurements before removed outlier meas')’

Save in ‘D:\Yitong\GitHub\thesis\_indoorLocalization\data-from-experiments\experiment\_12.Oct.2017.Hangar\record\_of\_HTerm\outlier\_removement\exper4\NumValuable measurements before-after removed outlier measVStime diff.fig’