Notation statement:

To clarify the characteristics of a variable, we use underscore "_" + notation
In "variable_t", "_t" means that this is a variable at some point in time, this is a scaler (Ex, variable at time t= 100)
In "variable_tsq", "_tsq" means that this is a time series variable, this is a vector list (Ex: variable from 0 to time t = 100)
In "variable_d", "_d" means that every scaler in the list of that variable will last for a period of time.
In "variable_s", "_s" means that this variable contains different scenarios, each scaler in that variable is unique.
For example:
u_d = [0,1,0]; t_d = [100,10,20]; means that u = 0 lasts for 100 timesteps, u=1 lasts for the next 10 timesteps, u = 0 lasts for the following 20 timesteps.

System model(SM): A,B,H,Q,R
System setup (SS): It contains the different input scenarios u_s, particular timestep ts, simulation setup u_d and t_d
measurements (z_tsq): The value observed over time by the sensor, this could come from simulation or real-world data
prediction (Pre): predicted states
estimation (Est): estimated states
Sigma (Sig): states likelihood
A: system transfer matrix
B: input matrix
H: observation matrix
Q: covariance of the process noise
R: covariance of the measurement noise
ts: a particular timestep. we need to use the planner to determine the error probabilities at that time step.
x0: initial state
ground_truth (g): ground truth data over time
The red box is what will be embedded in other groups
The blue box is the estimator box which will be run on agents\satellites
⊕: This symbol means that the current block will be run N number of times, and it also means that the output data stream will be accumulated N times