Tracking the states w/ UUV

1. Data Sync.
2. Bias initialization.
3. eskf model

IMU cb →

GPS cb →

ESKF →

$z = h(x)$

$x = \begin{matrix} P \\ V \\ R \end{matrix}$

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preview = 80

ESKF model

$x_t = \begin{bmatrix} p_t \\ v_t \\ R_t \\ b_{at} \\ b_{gt} \\ g_t \end{bmatrix}$ $\quad \tilde{\omega} \ \tilde{a}$ ← IMU

$\dot{p}_t = v_t$

$\dot{v}_t = R_t(\tilde{a} - b_{at} - \eta_a) + g$

$\dot{R}_t = R_t(\tilde{\omega} - b_{gt} - \eta_g)^\wedge$

$\dot{b}_{gt} = \eta_{bg}$

$\dot{b}_{at} = \eta_{ba}$

$\dot{g} = 0$

subscript w/ t := true state

$p_t = p + \delta p$

$v_t = v + \delta v$

$R_t = R\,\delta R$

$b_{gt} = b_g + \delta b_g$

$b_{at} = b_a + \delta b_a$

$g_t = g + \delta g$

nominal

$\dot{p}_t = v_t$

$\Rightarrow \dot{p} + \delta\dot{p} = v + \delta v$

$\therefore \delta\dot{p} = \delta v$ — ①

$\dot{b}_{gt} = \eta_{bg}$

$\Rightarrow \dot{b}_g + \delta\dot{b}_g = \eta_{bg}$ — ②

$\dot{b}_{at} = \eta_{ba}$

$\Rightarrow \dot{b}_a + \delta\dot{b}_a = \eta_{ba}$ — ③

$\dot{g}_t = 0$

$\Rightarrow \dot{g} + \delta\dot{g} = 0$ —

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$\dot{R}_t = R_t(\tilde{\omega} - b_{gt} - \eta_g)^\wedge$ — ⓐ

$R_t = R \circ Exp(\delta R)$ — ⓑ

from ⓑ

$\dot{R}_t = \dot{R}\,Exp(\delta\theta) + R\,\dot{Exp}(\delta\theta)$

$= R(\tilde{\omega} - b_{gt})^\wedge Exp(\delta\theta)$

$+$

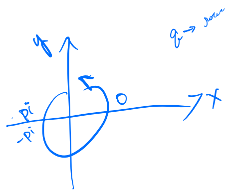
$R\,Exp(\delta\theta)\,\delta\dot{\theta}^\wedge$

from ⓐ & ⓑ

$R_t(\tilde{\omega} - b_{gt} - \eta_g)^\wedge$

$= R\,Exp(\delta\theta)(\tilde{\omega} - b_{gt} - \eta_g)^\wedge$

$\Rightarrow \{ R$



	xy z	Q	R	rotor const.	remark
1330	20N	380 / 880	1 / 1	0.02	
1350	20N	380 / 380	10 / 10	0.03	
14 00	20N	380 / 480	10 / 10	0.03	
14 10	20N	380 / 480	15 / 15	0.03	
1430	20N	300 / 300	1 / 1	0.03	
1440	20N	300 / 480	1 / 1	0.03	
1450	40N	300 / 480	1 / 1	0.03	
1545	40N	300 / 480	1 / 1	0.03	(fixed v_B)
1550	40N	300 / 300	1 / 1	0.03	
1600	10N	300 / 300	10 / 10	0.03	
1600	40	300 / 480	1 / 1	0.06	
1700	40	300 / 480	1 / 1	0.06	(cancel C(v) in MPC)
1710	40	300/480	1/1	0.03	(cancel C(v) in MPC)

EKF Stability proof

- $E[w_k w_k^T] = Q_k$

  $E[v_k v_k^T] = R_k$

- $x_{k+1} = f(x_k) + w_k$

  $z_k = h(x_k) + v_k$

- @ predict

  $\check{x}_k = f(\hat{x}_{k-1})$

  $\check{P}_k = F_k \hat{P}_{k-1} F_k^T + Q_k$

  ⇝ $F_k = \left[\frac{\partial f}{\partial x}\right]_{x=\hat{x}_{k-1}}$

  @ update

  $y_k = z_k - h(\check{x}_k)$

  $K_k = \check{P}_k H_k^T (H_k \check{P}_k H_k^T + R_k)^{-1}$

  ⇝ $H_k = \left[\frac{\partial h}{\partial x}\right]_{x=\check{x}_k}$

  $\hat{x}_k = \check{x}_k + K_k y_k$

  $\hat{P}_k = (I - K_k H_k)\check{P}_k$

證明前假設

- F_k is non-singular $\forall k \geq 0$
- R_k, Q_k are bounded from below

  where

  $$\bar{r} I \preceq R_k \qquad \forall k \geq 0$$
  $$\bar{q} I \preceq Q_k$$

  $\bar{r}, \bar{q} > 0$

- $\check{e}_k = x_k - \check{x}_k$

  $\hat{e}_k = x_k - \hat{x}_k$