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Schmidt-EKF-based Visual-Inertial Moving Object Tracking
Schmidt-Kalman Filter (SKF), In Which Target Measurements Do Not Update The Navigation States, However All Correlations Are Still Properly Tracked. This Allows For Both Consistent Modeling Of The Target Errors And The Ability To Update Target Estimates Whenever The ... May 2th, 2024
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Chapter 5 Moving Object Detection And Compression In IR ... Simulations Results On SH4- ... (12) $T_h = \theta^h \mathbf{F}^{3/4} t$ (13) $T_l = \theta^l \mathbf{F}^{3/4} t$ (14) In Our Experiments, We Set $\theta^h = 3:4$, $\theta^l = 0:8$ θ^h And $L = 16$.
2.2 MTI Algorithm Results Figure 5.1 Shows The Object Detection Result For Frame 200 And 300 On An IR Sequence (IRse Jul 2th, 2024)
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