

Index

- acceleration, inertial 401
 accelerometer 181, 398, 406
 accelerometer, MEMS 406
 algorithm, A* 664, 665
 algorithm, Bayes's filter 358, 368 algorithm,
 best first search 655
 algorithm, bicycle, Lagrange 214
 algorithm, bicycle, velocity-driven 211
 algorithm, blob coloring 529
 algorithm, breadth first 660
 algorithm, conjugate gradient 162 algorithm,
 D* 683, 686
 algorithm, Dijkstra's 661, 662
 algorithm, Gaussian elimination 131
 algorithm, Gauss-Newton 144
 algorithm, gradient descent 141, 150
 algorithm, grassfire 660 algorithm, Kalman
 filter 343
 algorithm, least squares 10, 144, 160, 195,
 218, 219, 262, 308, 309, 314, 373, 434,
 601, 614, 618, 626
 algorithm, Levenberg-Marquardt 143, 375
 algorithm, line search 141, 146, 149, 161, 617
 algorithm, midpoint 171 algorithm, reduced
 gradient 149
 algorithm, rootfinding 10, 117, 136, 137, 141,
 145, 153, 163, 255, 259, 467, 470,
 601, 612
 algorithm, sequential planning 649
 algorithm, steepest descent 141
 ambiguity, phase 537
 amplitude, spectral 292
 angle, azimuth 70
 angle, Euler 77, 78, 414
 angle, heading 70, 220
 angle, pitch 70, 71, 72
 angle, roll 70, 71, 72
 angle, slip 254
 angle, yaw 70, 71, 72, 220
 approximation, first-order 76, 118, 121, 144,
 241, 256, 282, 305, 376, 475, 488
 array, focal plane 82, 561
 association, closest point 606, 610
 association, nearest neighbor 610
 assumption, fixed contact point 191
 assumption, Markov 354, 357, 367, 653
 attenuation 540, 556, 557
 attitude 9, 55, 70, 72, 80, 104, 111, 174, 180,
 217, 223, 253, 285, 371, 398, 409, 415,
 417, 422, 581
 attitude & heading reference system (AHRS)
 420, 421
 autoiris 558
 autonomy 9
 autonomy, deliberative 9, 640
 autonomy, perceptive 9, 493, 514
 autonomy, reactive 9, 435
 backlash 399
 backpointer 583, 654, 665, 671, 679, 683
 backtracking 141
 backtracking, in line search 141 bandwidth
 163, 401, 404
 baseline 535, 569
 basis 46, 47
 basis, cycle 96

692

INDEX

- bias 271, 404
- bias, gyroscope 289 bias, of gyro 289
- bias, stability of 301, 404 bias, user clock, in GPS 427
- blooming 560
- blur circle 548
- body, rigid 71, 157, 165, 188
- bolometer 561

- calculus, stochastic 294, 303, 304
- calibration 137, 260, 268, 271, 316, 338, 339, 530, 617
- camera 82, 548, 557
- camera, pinhole 82
- car, Dubins' 644
- car, Reeds-Shepp 645
- center, of rotation, instantaneous 177, 189, 197, 217
- centroid, dwell 393
- check, for reasonableness 637
- clothoid 248, 469, 500
- coefficient, damping 232
- collinearity 41
- collision, region of inevitable 506
- compass 327, 386, 398, 400
- complement, orthogonal 28
- completeness 500, 511, 643
- condition, transversality 476
- configuration 501
- consistency, global 585, 586, 624
- consistency, in mapping 594, 623, 624, 627
- consistency, local 585
- constant, spring 232
- constant, time 227, 443
- constraint, circular 375
- constraint, differentiated 158
- constraint, environmental 509
- constraint, holonomic 155, 162, 202
- constraint, hyperbolic 375
- constraint, in DAEs 152
- constraint, in pose fixing 372
- constraint, inconsistent 217
- constraint, loop 627
- constraint, nonholonomic 156, 173, 191, 201, 207, 466, 649
- constraint, path 509
- constraint, Pfaffian 191, 208
- constraint, Pfaffian differentiated 212
- constraint, redundant 62, 216
- constraint, rolling without slipping 10, 190, 202
- constraint, satisfaction in optimization 125, 151, 627
- control 7
- control, bang bang 451
- control, cascaded 446
- control, coordinated 438
- control, hierarchical 437
- control, linear quadratic regulator 480
- control, model follower 450
- control, model predictive 253, 255, 473, 482, 494
- control, model referenced 447
- control, modern 453
- control, nonlinear 457
- control, optimal 477, 487, 495, 643
- control, optimal for LQR 481
- control, parametric optimal 490
- control, PID 444
- control, predictive 220
- control, receding horizon 482
- control, visual servo 465
- controllability 226, 453, 457, 460
- convexity, in optimization 120, 473
- convolution 497, 524
- coordinate 18, 49
- coordinate, homogeneous 42, 43
- coordinate, image 83
- coordinate, projective 42
- coordinate, scene 83
- coordinatization 182
- correlation 525, 602
- correlation, in SLAM 637
- correspondence, in localization 599, 606, 608, 611, 615
- correspondence, in stereo 569
- correspondence, in visual odometry 618, 620
- cosine, direction 80, 414
- cost-to-go 478, 661, 666, 676
- covariance 16, 144, 276, 282, 292, 296, 302, 311, 317, 366, 377, 379, 389, 392, 395, 527, 566, 583, 615, 633
- covariance, least squares 308
- criterion, Rayleigh 543, 544
- cross section 544
- curvature, Gaussian 531
- curvature, mean 531
- curvature, principal 531

- curvature, radius of 188, 221
 cycle 102
 cycle, in graph 97

 damping, critical 442
 data, aging of 586
 data, ephemeris, in GPS 426
 dead reckoning 10, 279, 302, 317, 332, 371, 385
 decrease, sufficient 140
 degeneracy 374
 density, spectral 304
 density, spectral, cross power 291
 density, spectral, power 291, 293
 depth, versus range 286
 derivative, as comparison 520
 derivative, Laplacian 521
 derivative, matrix product rule 36
 derivative, numerical 470
 derivative, rotation matrix 79
 derivative, vector 180
 descent, gradient 147, 486, 655, 657
 deviation, Allan 299, 300
 deviation, magnetic 400
 deviation, standard 276
 diagram, block 230
 diagram, contour 380
 diagram, generic block 436
 diagram, Jeantaud 189
 diagram, Venn 348
 diagram, Voronoi 505, 653
 difference, central 517
 difference, finite 486, 517
 difference, sum of absolute 526
 difference, sum of squared 526
 diffusion 304
 diode, laser 552
 direction, descent 140
 direction, disallowed 123, 154, 156, 190, 201, 207, 217
 directivity 539
 discriminant 233
 discriminant, Fisher's 567
 disparity 569
 disparity, in stereo 286, 569, 620
 dispersion 540, 554
 displacement, history point 243, 390
 distance, Mahalanobis 274, 278, 337, 566
 distance, stopping 246

 disturbance 436
 drift, in dead reckoning 585
 drift-off, in constrained dynamics 163
 dynamics, augmented system 151
 dynamics, Lagrange 151, 157, 160
 dynamics, Lagrange, augmented formulation 151
 dynamics, perturbative 243, 387

 Earth rate 415, 421
 edge 517, 518
 edge, detection of 515
 eigenvalue 28, 127, 238, 279, 455, 456, 462, 527, 531, 567, 573, 607
 eigenvalue, assignment of 455 eigenvector 28, 238, 279
 elevation 70
 encoder, incremental 399
 encoder, optical 399
 encoder, quadrature 399
 encoder, string 399
 encoder, wheel 330
 ensemble 289
 equation, articulated wheel acceleration 186
 equation, articulated wheel velocity 185
 equation, Bellman 479, 484
 equation, Coriolis 177, 180, 420
 equation, differential-algebraic 151
 equation, Euler-Lagrange 475, 478
 equation, homogeneous 239
 equation, linear perturbation 241
 equation, linear variance 306
 equation, normal 132
 equation, radar 286, 563
 equation, Ricatti 481
 equation, state 236
 equation, wheel 192
 equation, wheel, offset 192, 194
 error, alongtrack 438, 460
 error, crosstrack 438, 460
 error, forms of 271
 error, gyro bias 395
 error, in acceleration 403, 416
 error, multipath 431, 544
 error, random 379
 error, scale factor in velocity 395
 error, steady-state 443
 error, systematic in triangulation 376

- estimate, maximum likelihood 275, 308, 356
 estimation, maximum likelihood 307, 601
 event, independent 347
 event, mutually exclusive 346
 expectation 274
 exponential, matrix 25, 80, 113, 237, 319
 exponential, vector 105
- feasible 153, 451
 feature 116, 332, 384, 526, 565, 582, 597, 599, 606, 614, 623, 625, 632
 feature, detection of 516
 feature, matching of 597
 feature, tracking of 516
 feedback 323, 436, 439
 feedback, output 454
 feedback, state 454
 feedforward 322, 448, 450
 fiducial, camera 607
 fiducial, retroreflective 530
 field of view, instantaneous 553
 field, potential 504, 657
 field, proximity 504
 filter, Bayes' 358
 filter, direct 322
 filter, error state 322
 filter, Gaussian 520, 523
 filter, high pass 517
 filter, indirect 322
 filter, Kalman 277, 306, 313, 373, 632
 filter, Kalman, complementary 325
 filter, Kalman, extended 314, 323, 324
 filter, Kalman, linear 319
 filter, Kalman, linearized 314, 322
 filter, linear Kalman 320
 filter, linearized Kalman 325
 filter, low pass 523
 filter, matched 526
 filter, particle 368
 filter, total state 322
 filter, transmission of 549
 filtering 272
 fix, pose or position 365, 366, 371, 372, 376, 378, 384, 385, 425, 427, 591, 628
 focal length 287, 547
 force, apparent 402
 force, applied 157
 force, constraint 157, 158
 force, equipollent 214
 force, friction 444
 force, specific 181, 252, 401, 405
 formula, Lensmaker's 546
 formula, Sherman-Morrison 31
 formula, thin lens 547
 frame 47, 94
 frame, body 10, 71, 78, 111, 185, 189, 208, 209, 221, 327, 409, 415, 420, 589
 frame, contact point 72
 frame, coordinate 18, 97
 frame, Earth 412
 frame, equivalent 175
 frame, fixed 176, 177, 181, 412
 frame, head 72
 frame, inertial 412
 frame, moving 176, 177, 181, 203, 211, 402, 412
 frame, navigation 71, 78, 111, 415, 418
 frame, positioner 71
 frame, reference 15, 48, 174
 frame, sensor 72
 frame, vehicle 71, 191, 202, 207, 220, 345, 409, 412, 418, 421
 frame, world 10, 71, 165, 185, 192, 203, 220, 224, 332, 460, 589, 594, 625
 frames, for WMR kinematics 192
 freedom, degree of 56, 58, 59, 60, 62, 70, 201, 209, 220, 405, 437, 463, 469, 486, 511, 606, 608, 615, 625
 freedom, gauge 625
 frequency, natural 232
 function 13, 24
 function, autocorrelation 290
 function, belief 358
 function, convex 120
 function, correlated 290
 function, cost 120
 function, crosscorrelation 291
 function, forcing 227
 function, navigation 505, 509
 function, objective 120, 607
 function, optimal return 478
 function, penalty 127, 147, 487, 629
 function, transfer 230, 238
 function, unit impulse 292
 function, utility 120
 function, value 478
 functional 14, 168, 474

INDEX

695

- gain, derivative 441
- gain, integral 444
- gain, Kalman 298
- gain, of transfer function 231
- gain, proportional 441
- gate, validation in data association 337, 637
- Global Positioning System 425
- GPS, differential 432
- gradient, conjugate 160
- gradient, reduced 149
- graph 91
- graph, search 648, 654, 669, 670, 679, 686, 688
- gravitation 372, 401, 403, 413, 414, 476, 623
- gravity 413, 414
- grid, certainty 359, 631
- grid, evidence 359, 581
- grid, occupancy 359, 581, 598
- guidepath 651
- gyrocompassing 418
- gyroscope 289, 327, 398, 406
- gyroscope, dynamically tuned 407
- gyroscope, fiber optic 408
- gyroscope, MEMS 408
- gyroscope, optical 407
- gyroscope, ring laser 408
- gyroscope, tactical grade 408

- Hamiltonian 477, 479, 489
- hazard 497
- heuristic, consistent 667
- high centering 497
- histogram 529, 530
- holonomic 217
- homotopy class 647
- horizon, control 482
- horizon, planning 675
- horizon, prediction 482

- identification, equation error formulation 260
- identification, integrated equation error formulation 263
- identification, output error formulation 262
- identification, system 260
- image 593
- image, formation of 596 image, panoramic 550
- image, processing of 515

- image, range 88, 589
- image, rectification of 618 image, thermal 562
- implements 6
- inclinometer 398, 401, 411, 421
- inequality, triangle 667
- infrared 560
- inlier 609
- innovation 298, 312
- innovation, covariance of 312, 337
- integral, Fresnel 191
- integral, matrix superposition 237, 305, 388
- integral, superposition 390
- integral, vector superposition 237, 242, 388
- integration, Euler 169
- integration, midpoint 171
- integration, Runge-Kutta 171
- integration, stochastic 291, 301, 332
- interlace 559

- Jacobian, compound-inner pose 100, 334, 628
- Jacobian, compound-left pose 98, 336, 616, 619
- Jacobian, compound-right pose 99, 335
- Jacobian, determinant of 378
- Jacobian, imaging 86
- Jacobian, inverse pose 101, 334
- Jacobian, measurement 314, 373
- Jacobian, pose 102, 608
- Jacobian, right-left pose 99, 335

- kinematics 58
- kinematics, articulated wheel 185, 186
- kinematics, constrained 205
- kinematics, generic planar vehicle 221
- kinematics, generic velocity 222
- kinematics, inverse 62
- kinematics, manipulator 64
- kinematics, offset wheel 192, 195

- ladar 535
- Lagrangian 126, 133, 474, 477, 489
- landmark 2, 70, 332, 334, 336, 341, 372, 374, 384, 417, 426, 431, 516, 580, 583, 598, 623, 632, 636
- laser rangefinder 72, 83, 84, 283, 286, 555
- law, Newton's of gravitation 414
- law, Newton's second 405

- law, Snell 542
- learning, supervised 566
- least squares 132, 217
- lemma, matrix inversion 31
- lens, aperture of 548
- lens, depth of field of 548, 549
- lens, distortion due to 549
- lens, thin 546
- level curve 118, 119
- level surface 118, 119
- lidar 88, 535
- lidar, colorized 555
- light, structured 536, 568
- limit, diffraction 539
- line, epipolar 569
- linearization 118, 136
- linearization, of state space models 256
- linearized 322
- localization 8, 316, 332, 365, 370, 514, 515, 530, 579, 583, 585, 595, 627
- localization, of objects 596, 617
- localization, simultaneous with mapping (SLAM) 594, 623, 632
- localization, visual 549, 593, 595, 600
- longitude, geodetic 429
- loop, closure 623
- loop, rebalance 401

- magnetometer 400
- manipulator 59
- map 7, 332
- map, cost 670
- map, depth 582
- map, elevation 581
- map, obstacle 670
- map, scrolling 587
- map, terrain 589
- map, topological 587
- map, wrapping 587
- mapping 7, 595
- marginalization 349
- material handling 2
- matrix 16
- matrix, column space 28, 132
- matrix, covariance 238, 278, 281
- matrix, Denavit Hartenberg 59
- matrix, determinant of 26, 377, 382
- matrix, Hessian 35, 117, 122, 124, 142, 144, 146, 521, 531
- matrix, information 313
- matrix, input transition 237, 243, 388
- matrix, invertible 27
- matrix, Jacobian 35, 66, 67
- matrix, measurement 236, 318
- matrix, multiplication of 22
- matrix, nonsingular 27
- matrix, nullity 28
- matrix, nullspace 28, 155
- matrix, observation 318
- matrix, positive definite 27
- matrix, process noise distribution 318
- matrix, projection 40, 155
- matrix, range 28
- matrix, rotation 44, 52, 79, 110
- matrix, row space 28
- matrix, scatter 567
- matrix, Schur complement 30, 31
- matrix, singular 27
- matrix, skew 23, 76, 79, 80, 182
- matrix, system dynamics 236
- matrix, trace of 377
- matrix, transition 236, 241, 318
- mean 275, 276
- measurement 318
- measurement, camera 596
- measurement, for maps 336
- measurement, GPS 427
- measurement, predictive 323
- measurement, wheel 330
- message, navigation, in GPS 426
- method, constrained Gauss-Newton 147
- method, Euler's 168
- method, Midpoint 170
- method, Newton's 10, 136, 139, 142, 144, 150, 259, 470, 471, 486, 614
- method, Newton's constrained 146, 490
- method, quasi-Newton 142
- method, Rayleigh-Ritz 487
- method, Runge-Kutta 171
- method, shooting 487
- minimum (extremum), constrained local 126
- minimum (extremum), global 120
- minimum (extremum), local 120, 121, 122
- mirror, omnidirectional 550
- model, 2D mobile robot 327
- model, Bayesian motion 366, 367
- model, Bayesian sensor 351, 366
- model, bicycle 196, 209

- model, camera 82, 548
- model, constrained form 201
- model, DAE form 204
- model, differential equation as 168
- model, dynamics 157
- model, environment 499
- model, error 271
- model, force driven bicycle 212
- model, forward kinematic 58
- model, fully actuated WMR 221, 223, 242
- model, generalized bicycle 197
- model, image formation 464
- model, inertial sensor 404
- model, inverse 508
- model, inverted sensor 365
- model, kinematic 154
- model, laser rangefinder 83, 84
- model, lidar error 286
- model, manipulator 61, 67
- model, measurement 319
- model, measurement in SLAM 634
- model, mechanism 58, 61, 66
- model, mobile robot 168
- model, object 593
- model, particle 246
- model, predictive in planning 642
- model, reference 447
- model, scene 499
- model, sensing 330
- model, sensor 82, 360
- model, slip 215
- model, sonar 361
- model, state space 316
- model, suspension 218
- model, system in estimation 220
- model, system in SLAM 633
- model, systematic 272
- model, tire 216
- model, underactuated WMR 222
- model, vehicle 71, 499, 669
- model, velocity driven bicycle 208
- model, wheeled mobile robot 187
- model, world 650
- modulation, amplitude 537
- moment, of error 388, 395
- mosaicking, image 619
- motion, blur due to 555, 583, 590
- motion, estimation of 617
- motion, state of 15, 174
- multiplier, Lagrange 127, 154, 159
- navigation 7
- navigation, free inertial 416
- navigation, inertial 410, 413
- navigation, satellite 377, 417, 425
- negative, false 574
- neighborhood 518
- network 91
- network, cyclic 95, 96
- network, pose 90, 93, 94
- node, expansion of in planning 654
- noise 271, 404, 515
- noise, density of 293, 304
- nonlinearity 404
- normalization, statistical 522
- notation, implicit layout 37, 38, 117, 122, 142
- notation, implicit sum 32 notation, numerical methods 117
- nullity 28
- object, detection of 516
- object, recognition of 515, 516
- objective, gradient of 121
- observability 264, 321, 371, 454
- observer, in control theory 456
- obstacle 496
- obstacle, C-space 501, 505, 652, 670
- obstacle, detection of 516
- obstacle, list of 581
- obstacle, negative 497, 575
- occupancy 503
- odds 346
- odometry 220, 302, 303, 386
- odometry, differential heading 387
- odometry, direct heading 386
- odometry, error propagation 389, 395
- odometry, integrated heading 387
- odometry, visual 516, 620
- operand, conformable 21
- operation, aligning 47, 54
- operator 42, 45, 51
- operator, Harris 527
- operator, kernel, in image processing 517
- operator, mask, in image processing 517
- operator, normalization 521
- operator, reflection 83
- operator, rigid 44

- operator, Sobel 519
- operator, template, in image processing 517
- operator, texture, in image processing 527
- optical flow 516
- optimal estimation 8, 307, 314, 338, 346, 372, 404, 597
- optimality, conditions 124
- optimality, principle of 478, 653
- optimization, constrained 124, 219, 488, 629
- optimization, nonlinear 139
- optimization, quadratic 127
- optimization, unconstrained 125, 626
- optimization, variational 125, 473
- orientation 70
- orientation, Jordan's update 81, 415
- orthonormality 51
- oscillator, damped 232
- outlier 271, 609
- overshoot, percent 443

- parameter, extrinsic 595
- parameter, intrinsic 596
- particle 187
- patch, contact 190
- path 467, 500
- path, cost of 499
- path, following of 461, 482, 483, 490
- path, relaxation of 259
- perception 7
- perturbation 241
- perturbation, feasible 123
- pixel 558
- pixel, footprint of 553
- place, recognition of 516, 612
- plane, reflection 83
- plane, tangent 119, 124
- plane, tangent, constraint 123
- planner, admissible 648, 657, 666
- planner, anytime 677
- planner, complete 659
- planner, feasible 649, 657
- planner, optimal 648
- planning 7
- planning, coverage 641
- planning, depth-limited 675
- planning, motion 641
- planning, path 641
- planning, repair of plan 680
- point 19, 45
- point, cloud of 670
- point, contact 189
- point, feasible 123
- pole, geographic north 400
- pole, of system 230
- policy, in planning 478, 655, 679
- polynomial, characteristic 228, 230, 233
- pose 66, 70, 93, 94, 97, 370
- pose tag 583
- pose, determination of 612
- pose, estimation of 370
- pose, jumps in 592
- pose, local 592
- pose, refinement of 612
- pose, relative 626
- pose, tracking of 612
- pose, warping of sequence 628
- positive, false 574
- precession 407
- precision, dilution of 377, 378, 381, 383
- precision, dilution of, geometric 377
- prediction, motion 386
- principle, branch and bound 655
- principle, relativity 175
- principle, virtual work 159
- prior map 673
- priority queue 661
- probability 272
- probability, conditional 307, 310, 347
- probability, conditional density function 273
- probability, density 272
- probability, density function 347
- probability, Gaussian density function 271, 274
- probability, joint density function 273
- probability, joint mass function 348
- probability, marginal distribution 349
- probability, mass function 272, 347
- probability, normal distribution 271
- problem, correspondence 464, 537, 569, 606
- problem, data association 337, 597, 637
- problem, map insertion 586, 612
- problem, missing parts 535, 582, 609
- problem, revisiting 586, 595, 630, 632
- problem, sampling 582, 590
- process, ergodic random 290
- process, random 289
- process, sequential decision 649, 653

INDEX

699

- process, stationary 291
- process, stationary random 290 process, unbiased random 290
- product, vector dot 22, 24, 108, 518
- product, vector outer 23, 84, 105, 389, 636
- programming, dynamic 478, 653
- programming, nonlinear 124
- projection, reduced gradient 147
- pseudoinverse 132, 135
- pseudoinverse, left 133, 377
- pseudoinverse, right 134
- pseudomeasurement 340
- pseudorange, in GPS 426, 427

- quaternion 103, 415
- quaternion loop 103
- quaternion, identity 112
- quaternion, unit 108

- radiation pattern 539
- radius rate, Pfaffian 204
- radius, dwell 394
- radius, Pfaffian 203
- ranging, techniques for 535
- ranging, time-of-flight 537
- rank, deficiency of 27
- rank, full 27
- rank, of matrix 321
- rate, Pfaffian 203
- ratio, damping 232
- ratio, signal-to-noise 559
- reference frame 370, 411, 414, 515
- reflection 541
- reflection, diffuse 543
- reflection, specular 543
- reflector, Lambertian 543
- refraction 541
- region, trust 142
- regularizer 133
- regulator 436
- response, frequency 231
- response, impulse 228
- response, step 228, 232
- response, zero input 240
- rigidity 407
- road, following of 602
- rollover 250

- rollover, maneuver-induced 250
- rotation, differential 76
- rotation, instantaneous center of 188
- rotation, rigid body 75, 109
- rule, Bayes's 349, 350, 357, 358
- rule, Leibnitz' 39, 257

- sampling 120
- saturation 405
- scalar 105
- scalar, multiplication of 22
- scale factor 42, 271, 404
- scan, progressive 559
- scanner, azimuth 85, 283
- scanner, elevation 90
- scene 534, 593
- scene, understanding of 515
- search, breadth first 660
- search, depth first 660
- search, lazy 671
- search, line 140, 141, 149
- segmentation 516, 529
- sensor, active 534
- sensor, aiding 416
- sensor, imaging 534
- sensor, nonimaging 534
- sensor, passive 534
- sensor, radiative 534
- sensor, scanning 534
- sequence, disturbance 318
- sequence, measurement noise 318
- sequence, process noise 318
- servo 436
- servoing, visual 463, 464, 465, 472
- set point 436
- set, feasible 123
- shadow, range 582
- signal, alignment of 597
- signal, control 227, 648
- signal, error 436, 440
- signal, input 227, 436
- signal, output 436
- signal, processing of 515 signal, reference 436
- signal, white 290, 304
- singularity 67
- sonar, distortion of 557

700

space, configuration (C-space) 58, 501, 650
 space, free 503
 space, function 485
 space, hazard 498
 space, Hilbert 485
 space, reachable workspace 506
 space, state 235, 453, 648
 space, task 58
 space, volumetric C-space 502
 space, workspace 58, 62, 501
 speed, of light 540
 speed, of sound 540
 spiral, Cornu 469
 spiral, polynomial 469
 stability 440
 stability, margin of 180, 181, 253
 stability, of dynamical system 238
 stability, of vehicle 250
 stability, pyramid of 252, 253
 stability, static factor of 249, 251
 stabilization, computational 591
 standoff 557
 state 174
 state vector augmentation 338
 state, estimation of 7, 370, 514
 state, of a system 235, 236
 statistic 274, 276
 steering, Ackerman 196
 steering, Differential 195
 steering, four wheel 198
 substitution, back 222
 subtraction, background 584
 system, closed-loop 439
 system, coordinate 15, 174
 system, coordinate, ECEF 429
 system, drift-free 240
 system, dynamical 227
 system, first-order 227
 system, homogeneous 27
 system, linear time invariant 227
 system, monotone 240
 system, motion dependent 240
 system, open-loop 439
 system, overdetermined 132
 system, reference 448
 system, reversible 240
 system, second-order 232
 system, strapdown 403

INDEX

system, underactuated 222
 system, unstable 228, 440
 tensor 17
 tensor, derivative of 38
 tensor, multiplication of 37
 terrain, following of 10, 73, 204, 217, 218, 226, 285, 386, 471, 501
 theorem, Euler's 75
 theorem, of plane curves 459
 theorem, rank-nullity 29
 theorem, total probability 349
 theorem, transport 177
 time of flight 427
 time tag 583
 time, rise 443
 time, settling 443
 tradeoff, accumulation/distortion 585
 trajectory 467, 500
 trajectory, following of 458, 459
 trajectory, generation of 450, 451, 466, 467, 470, 483
 trajectory, infeasible 467
 trajectory, reference 240
 transform 51
 transform, acceleration 178, 181, 402
 transform, affine 41
 transform, bound 18
 transform, collineatory 41
 transform, distance 652
 transform, free 18
 transform, grassfire 529
 transform, homogeneous 41, 51, 53, 72, 82, 93, 104, 285, 548, 596
 transform, Householder 84
 transform, Laplace 229
 transform, nonlinear 281
 transform, of coordinates 281
 transform, orthogonal 41
 transform, rigid 52
 transform, RPY 73
 transform, similarity 278
 transform, velocity 177
 transmission 541
 tree, search 654, 659, 679
 tree, spanning 96, 654, 658
 tree, transform 92
 triangulation 68, 372
 triangulation, active 536

INDEX

701

- triangulation, passive 536
- triangulation, stereo 535
- trilateration 372, 536
- uncertainty 270
- uncertainty, total 302
- uncertainty, transformation of 283
- unit, inertial measurement (IMU) 409
- value, expected 274
- variable, random 289
- variable, unbiased random 282
- variable, uncorrelated 276, 283
- variance 275, 276
- variance, Allan 299, 404
- variance, of average 280
- variance, of continuous average 297
- variance, of continuous sum 296
- variance, of sum 279
- variance, reduction in filtering 314
- variation 474
- variation, magnetic 400
- vector 105
- vector, augmented state 339
- vector, bound 19
- vector, conjugate 161
- vector, costate 477
- vector, free 19
- vector, gradient 34, 117, 119, 122, 123, 132, 141, 142, 145, 161, 165, 202, 216, 262, 267, 286, 484, 502, 504, 509, 518, 527, 570, 612, 614, 647
- vector, input 168
- vector, measurement 307
- vector, output 236
- vector, residual 132
- vector, rotation 75
- vector, state 168, 307, 317, 318
- vector, unbiased random 271
- velocity, angular 78, 111, 190
- voxel 586
- walk, angle random 293, 300
- walk, integrated random 294
- walk, random 291, 293
- walk, rate random 294, 300
- waypoint 687
- WGS-84 429
- wheel, slip of 215, 255
- wheel, track of 251
- windup 445
- zero velocity update (zupt) 340