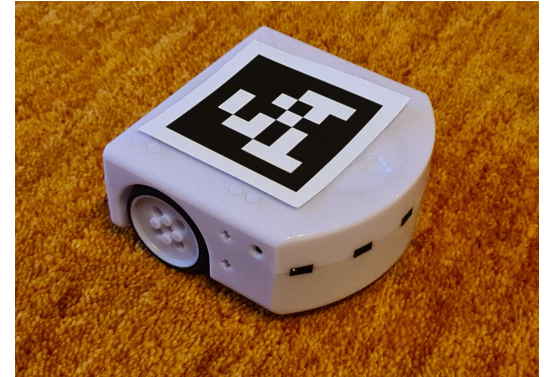


L8-C3 Kalman filter, covariance matrices

In a 2×2 m² setup, you estimate the pose (cartesian coordinates in mm and angle in rad) of the Thymio robot by using a Kalman filter based on the odometry and the vision of a high resolution camera (2000x2000 pixels) looking from the top and extracting the position and orientation of a marker. With this vision approach you can have a resolution of 1mm in position and 1 degree in angle. In the Kalman filter, as covariance matrix related to the measurement by the camera, your colleague uses an identity matrix. Does this make sense?



- A. Yes, because ...**
- B. No, because**