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Adaptive Two-stage Kalman Filter for SINS/Odometer Integrated Navigation Systems – ERRATUM

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The publisher apologises for the error on page 6 of this article where an incorrect expression of covariances was given in the last line of Section 2 (the ninth line from the top of the page). The term should read:

$$E[\mathbf{w}_k \mathbf{v}_j^T] = \mathbf{0}$$

REFERENCE

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