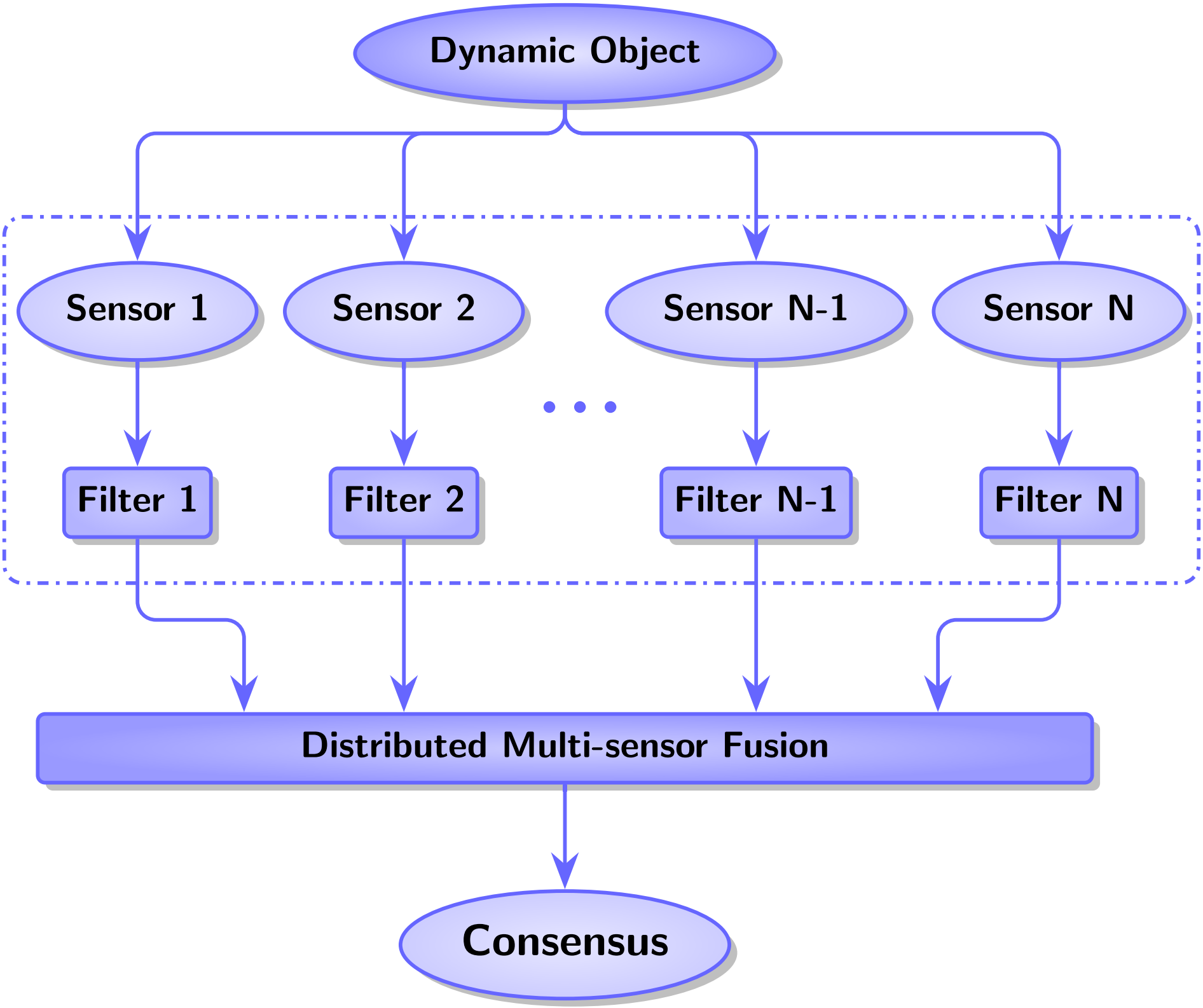
Dynamic Object
Sensor 1
Sensor 2
Sensor N-1
Sensor N
Filter 1
Filter 2
Filter N-1
Filter N
Distributed Multi-sensor Fusion
Consensus