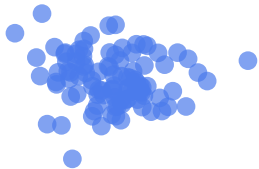
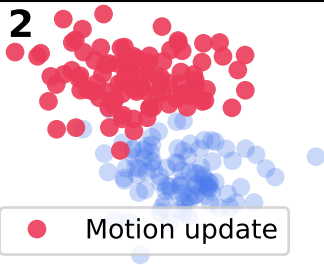


**1**

● Initial belief

**2**

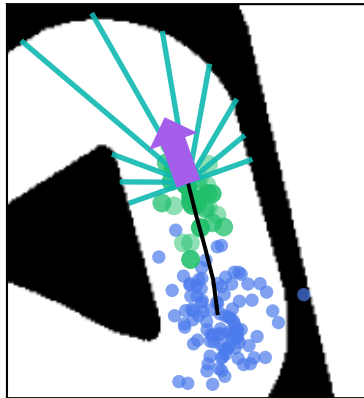
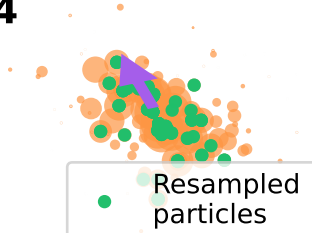
● Motion update

**3**

● Measurement weights

**4**

● Resampled particles



● Initial belief  
● Final belief  
— LiDAR beams  
— Vehicle path