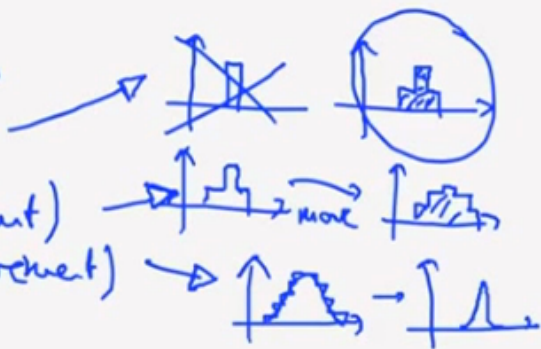# SLAM-C : Filtering

- Assign probabilities
- Distributions
- Convolution (movement)
  Multiplication (measurement)
- Bayes filter
- Histogram filter
- Distributions ⟶ Densities
  (discrete)   (continuous)

$$N(x; \mu, \sigma^2)$$

- Kalman filter