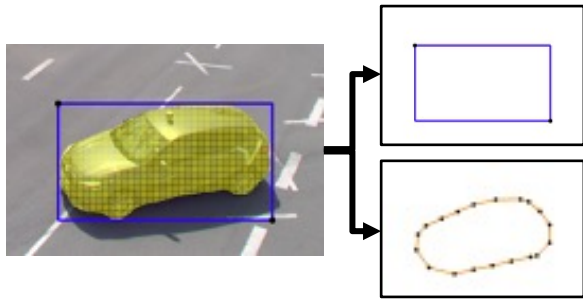


Measurements in **image space**

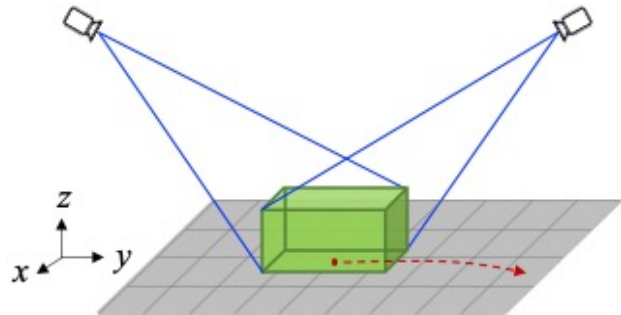


Detector output



?

State estimation in a common **world frame**



Multi-view tracking