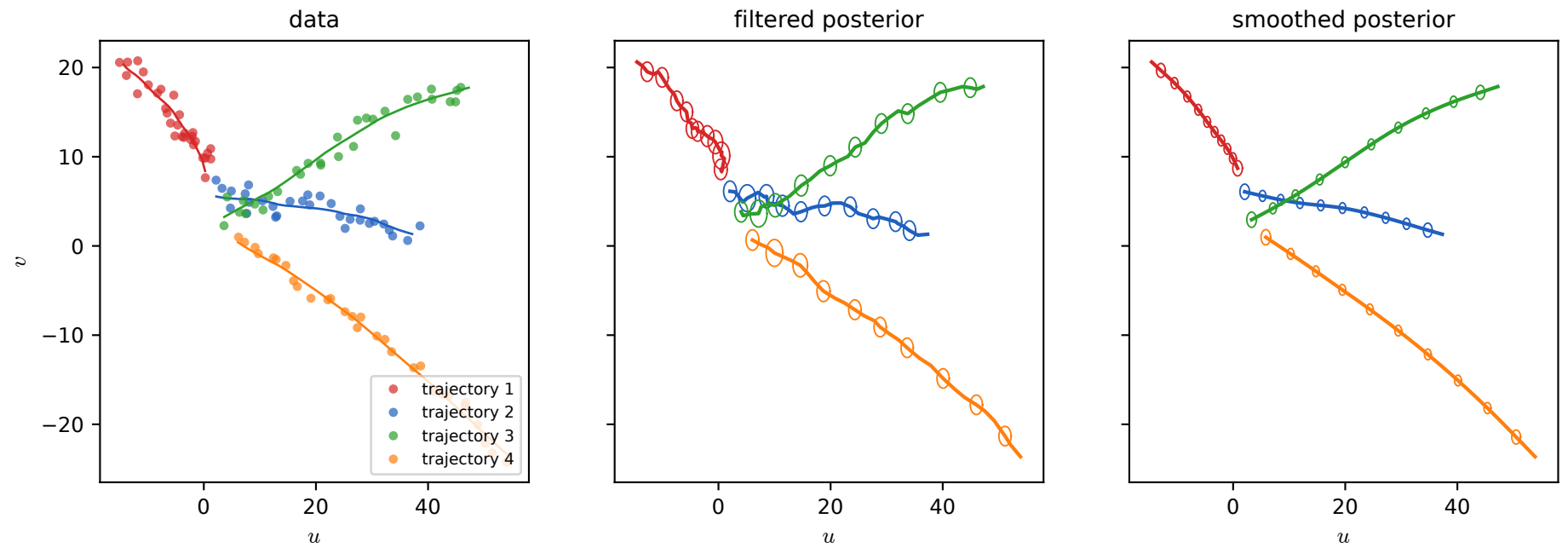

data
filtered posterior
smoothed posterior
trajectory 1
trajectory 2
trajectory 3
trajectory 4
v
u
u
u
20
10
0
−10
−20
0
20
40