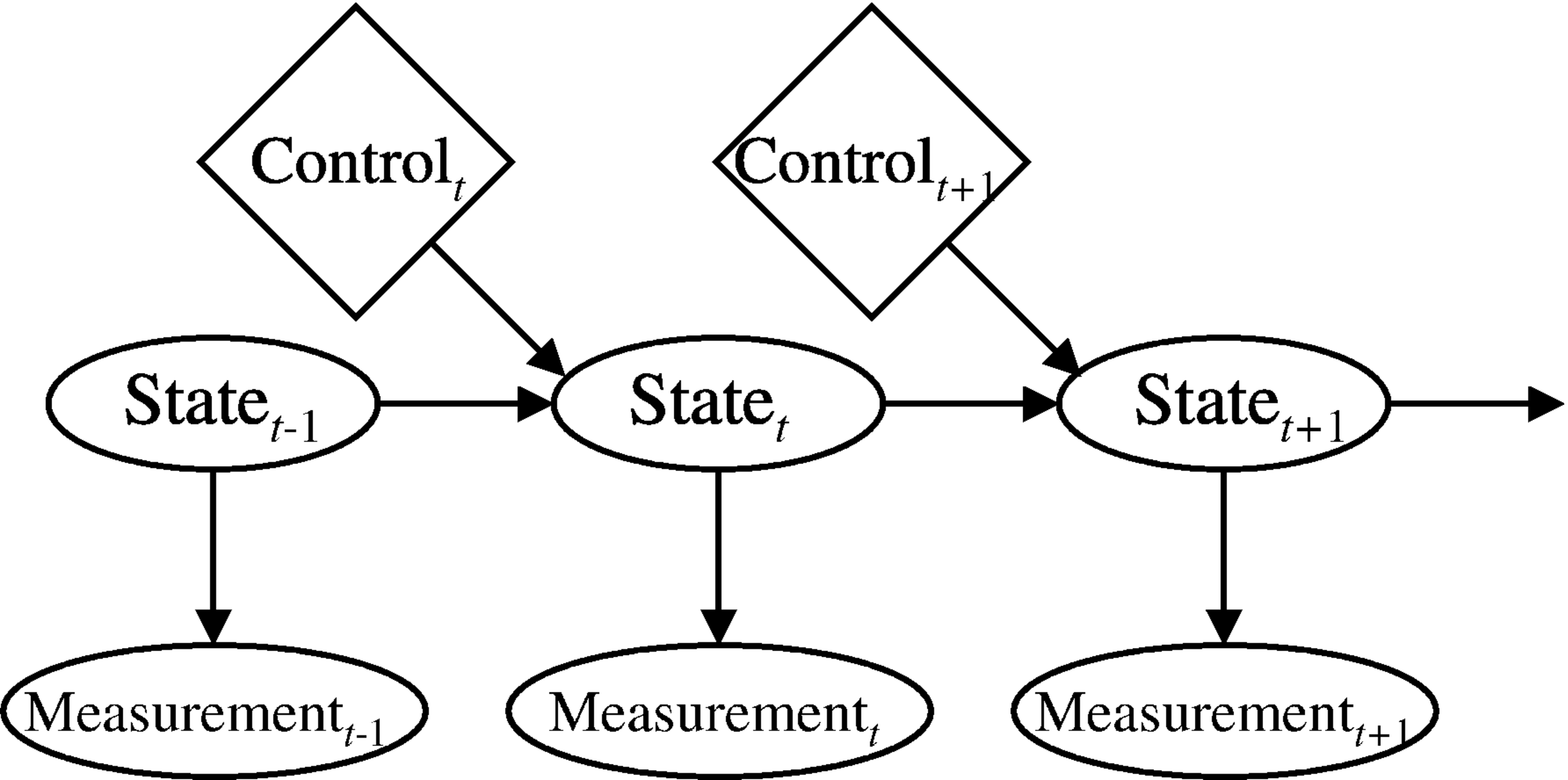
Control$_t$
Control$_{t+1}$
State$_{t-1}$
State$_t$
State$_{t+1}$
Measurement$_{t-1}$
Measurement$_t$
Measurement$_{t+1}$