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   Sommario/riassunto State estimation of an unknown number of objects remains a
                      challenging topic - despite the existence of theoretically bayes-optimal
                      multi-object-filters - due to numerous assumptions in the modeling
                      process. This thesis evaluates such filters in real multi-object-multi-
                      sensor scenarios and proposes necessary extensions to existing
                      models. The main application of the thesis is indoor pedestrian
                      tracking.