(1) Robot #1 calculates and transmits the "local estimate" of all 'L' parameters to the Fusion Filter.

(3) Fusion filter transmits the "complete/global estimate" of all "L" parameters to robot #1.

(2) Fusion Filter calculates the "complete/global estimates" of all 'L' parameters by combining its "local estimates" with the "local estimates" it receives from all other robots.