CLAIMS:

1. A tangible, non-transitory, machine-readable medium, comprising machine- readable instructions that, when executed by one or more processors of a machine, cause the machine to:

receive a tracked target context for a first tracked object from a first tracking sensor system tracking a first coverage area;

provide the tracked target context from the first tracking sensor system to a second tracking sensor system tracking a second coverage area different than the first coverage aera, wherein the second tracking sensor system is different than the first tracking sensor system; and

cause identification of a newly observed tracked target by the second tracking sensor system based upon the tracked target context from the first tracking sensor system, by

filtering-out a candidate from a set of candidates that the newly observed tracked target can be identified as based upon the tracked target context from the first tracking sensor system, by determining that the candidate is observed at a previous location outside a range of identified locations predicted to be reachable by the candidate during a time difference between a time the candidate was observed at the previous location and a time the newly observed tracked target was observed by the second tracking sensor system; and

providing the set of candidates without the candidate to the second tracking sensor system.

2. The machine-readable medium of claim 1, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

filter from the set of candidates a first subset of the set of candidates that the newly observed tracked target cannot be identified as based upon the tracked target context from the first tracking sensor system; and

identify, via the second tacking sensor system, the identification of the newly observed tracked target from the set of candidates without the first subset.

3. The machine-readable medium of claim 2, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

generate a blacklist based upon the first subset; and provide the blacklist to the second tracking sensor system.

4. The machine-readable medium of claim 2, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

generate a blacklist based upon the first subset; and provide the set of candidates without the blacklist to the second tracking sensor system.

5. The machine-readable medium of claim 1, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

filter from the set of candidates a second subset of the set of candidates that the newly observed tracked target can be identified as based upon the tracked target context from the first tracking sensor system; and

identify, via the second tracking sensor system, the identification of the newly observed tracked target from the second subset.

6. The machine-readable medium of claim 5, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

determine the second subset as a portion of the set of candidates observed at a previous location inside a range of identified locations predicted to be reachable by the candidate during a time difference between a time the set of candidates were observed at the previous location and a time the newly observed tracked target was observed by the second tracking sensor system.

7. The machine-readable medium of claim 5, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

generate a whitelist based upon the second subset; and provide the whitelist to the second tracking sensor system.

8. The machine-readable medium of claim 1, wherein the first tracking sensor system, the second tracking sensor system or both, comprise: a light detection and ranging (LIDAR) system,

a radio frequency identification (RFID) system, a computer vision system, a Time of Flight (ToF) system, a Millimeter Wave (mmWave) system, or any combination thereof.

9. The machine-readable medium of claim 8, wherein the second tracking sensor system comprises the LIDAR system.

10. The machine-readable medium of claim 1, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

determine a prediction confidence score indicative of a confidence level of the identification of the newly observed tracked target; and

gather additional tracking sensor system inputs for another identification of the newly observed tracked target in response to the prediction confidence score failing to meet a confidence threshold.

11. The machine-readable medium of claim 10, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to gather the additional tracking sensor system inputs by providing a direction to the newly observed tracked target to proceed to a tracking sensor system coverage area.

12. The machine-readable medium of claim 11, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to provide encouragement by incentivizing the newly observed tracked target to proceed to the tracking sensor system coverage area.

13. The machine-readable medium of claim 1, wherein the first tracked object comprises a different object type than the newly observed tracked target.

14. The machine-readable medium of claim 13, wherein the first tracked object comprises a vehicle and the newly observed tracked target comprises one or more persons.

15. The machine-readable medium of claim 1, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

receive training data indicative of a group of persons and associated attributes;

identify patterns in the associated attributes to identify grouping attributes indicating that persons should be grouped;

determine if the first tracked object is associated with the patterns; and

in response to determining that the first tracked object is associated with the patterns, identify the first tracked object as part of an active group.

16. The machine-readable medium of claim 15, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

determine if a second tracked object is a member of the active group, based upon the patterns, by:

determining an amount of time the first tracked object and the second tracked object have spent in a threshold proximity to each other; and

when the amount of time exceeds a threshold, associating the second tracked object with the active group.

17. The machine-readable medium of claim 15, comprising machine-readable instructions that, when executed by the one or more processors of the machine, cause the machine to:

determine if a second tracked object is a member of the active group, based upon the patterns, by:

associating a first weighted probability to the second tracked object, wherein the first weighted probability represents a likelihood that the second tracked object is a member of the active group;

associating a second weighted probability to the second tracked object, wherein the second weighted probability represent a second likelihood that the second tracked object is a member of the active group; and

when an addition of the first weighted probability and the second weighted probability exceeds a threshold value, associate the second tracked object with the active group.

18. The machine-readable medium of claim 17, wherein the first weighted probability is a value representative of an amount of time the second tracked object has spent in proximity to the first tracked object.

19. A computer-implemented method, comprising:

receiving tracking sensor system inputs comprising a tracked target context for a first tracked object from a first tracking sensor system tracking a first coverage area;

providing the tracked target context from the first tracking sensor system to a second tracking sensor system a second coverage area different than the first coverage area, wherein the second tracking sensor system is different than the first tracking sensor system; and

causing identification of a newly observed tracked target by the second tracking sensor system based upon the tracked target context from the first tracking sensor system, by

filtering-out a candidate from a set of candidates that the newly observed tracked target can be identified as based upon the tracked target context from the first tracking sensor system, by determining that the candidate is observed at a previous location outside a range of identified locations predicted to be reachable by the candidate during a time difference between a time the candidate was observed at the previous location and a time the newly observed tracked target was observed by the second tracking sensor system; and

providing the set of candidates without the candidate to the second tracking sensor system.

20. The computer-implemented method of claim 19, comprising:

determining a prediction confidence score indicative of a confidence level of the identification of the newly observed tracked target; and

gathering additional tracking sensor system inputs for another identification of the newly observed tracked target in response to the prediction confidence score failing to meet a threshold.

21. The computer-implemented method of claim 19, wherein the first tracked object and the newly observed tracked target comprise a first group of individuals.

22. A system, comprising:

a first tracking sensor system, configured to track a first tracked object in a first coverage area;

a second tracking sensor system, configured to track a second tracked object in a second coverage area different than the first coverage area; and

a contextual tracking system, configured to:

receive a tracked target context for the first tracked object from the first tracking sensor system;

provide the tracked target context from the first tracking sensor system to the second tracking sensor system different than the first tracking sensor system; and

cause identification of the second tracked object based upon the tracked target context from the first tracking sensor system, wherein the second tracking sensor system is different than the first tracking sensor system, by

filtering-out a candidate from a set of candidates that the second tracked object can be identified as based upon the tracked target context from the first tracking sensor system, by determining that the candidate is observed at a previous location outside a range of identified locations predicted to be reachable by the candidate during a time difference between a time the candidate was observed at the previous location and a time the second tracked object was observed by the second tracking sensor system ; and

providing the set of candidates without the candidate to the second tracking sensor system.

23. The system of claim 22, wherein the first tracking sensor system comprises a different sensor type than the second tracking sensor system.