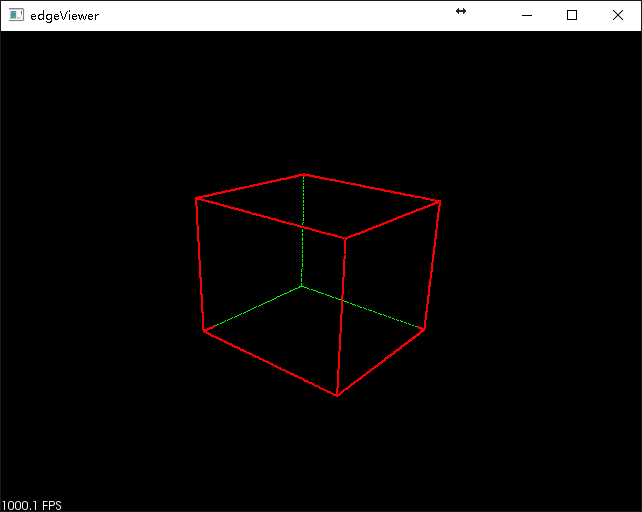
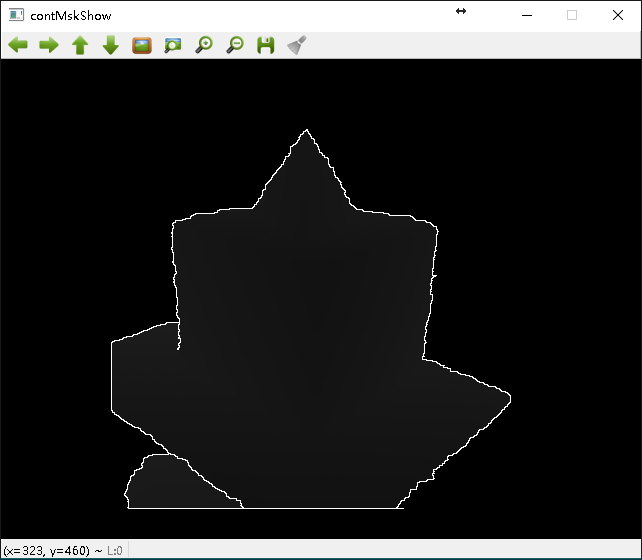
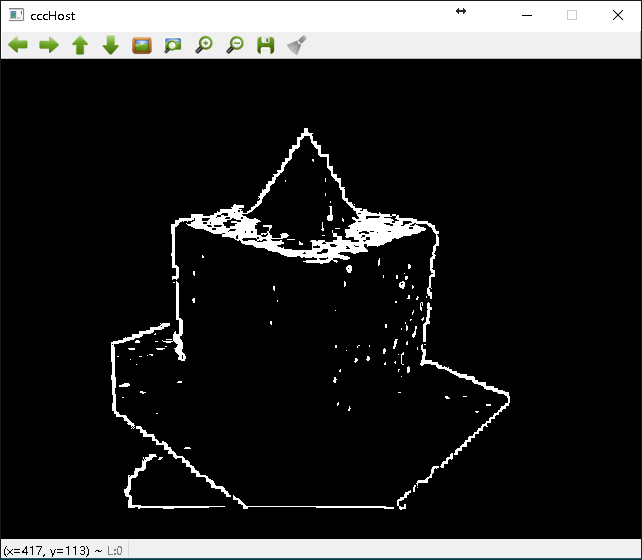
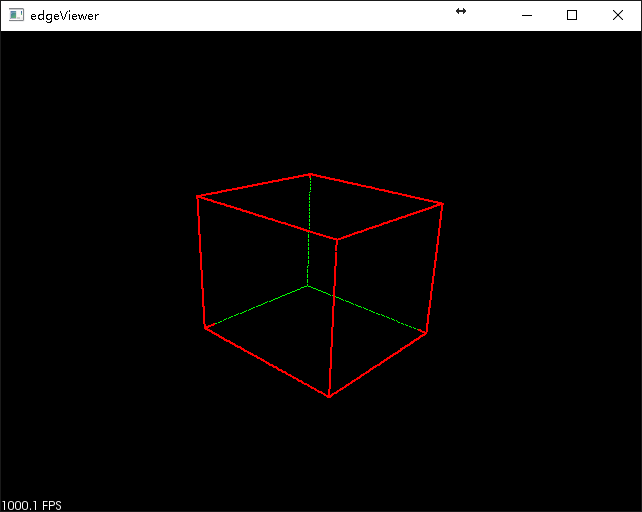
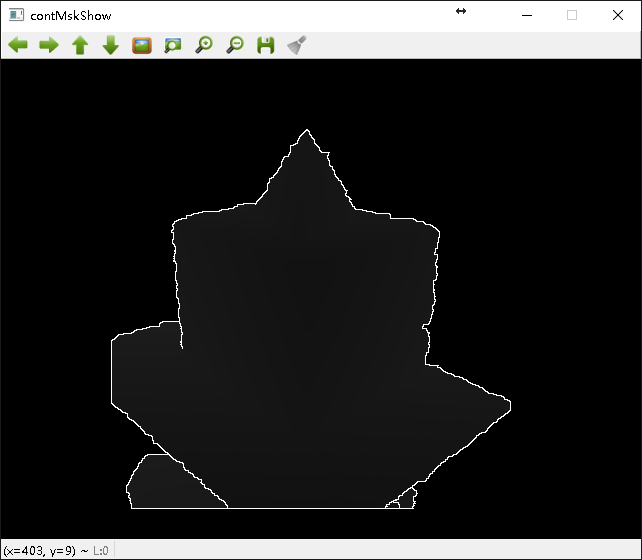
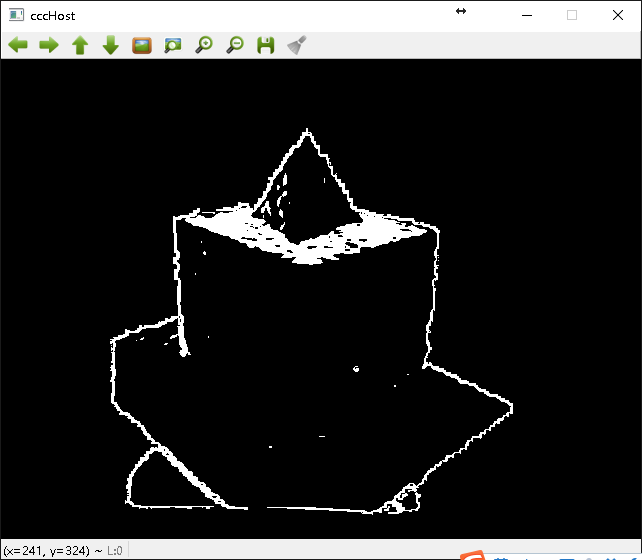
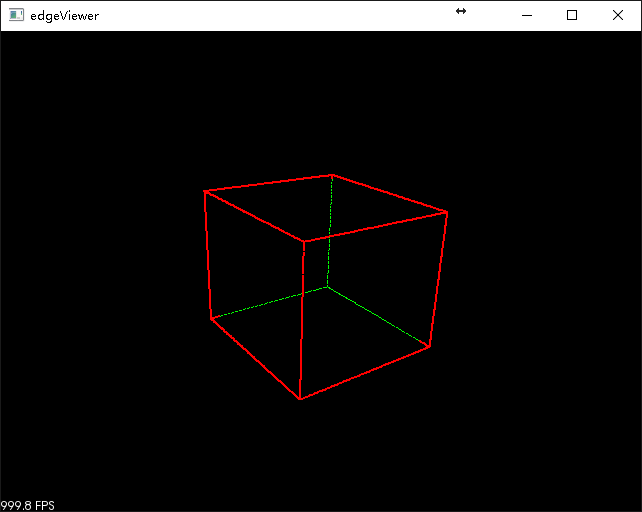
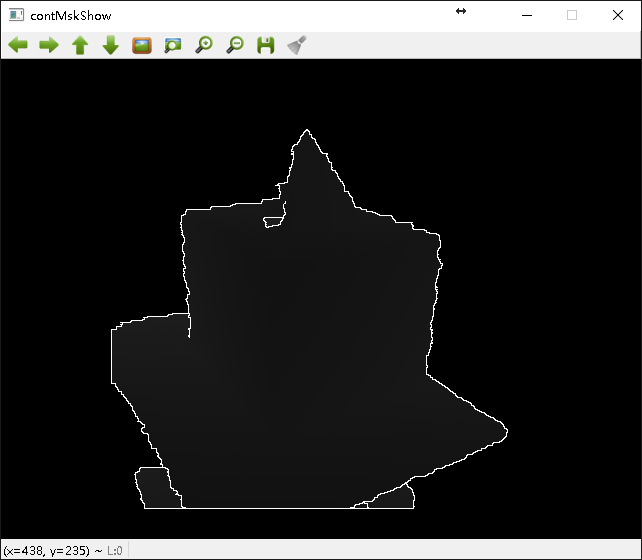
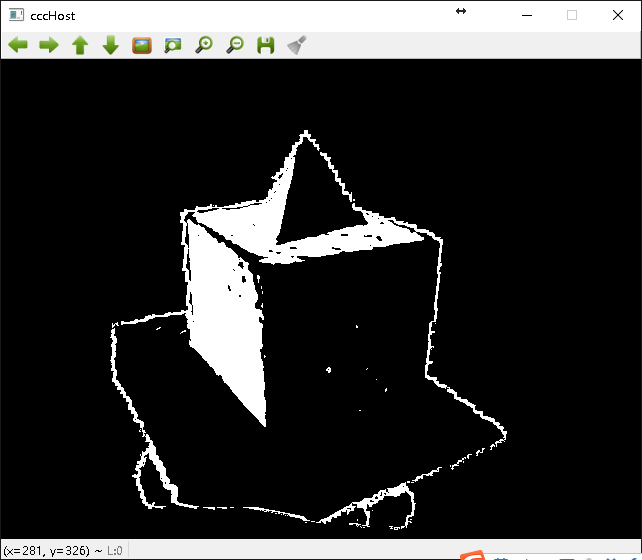
# 虚拟立方体轮廓与真实场景边缘提取结果对比

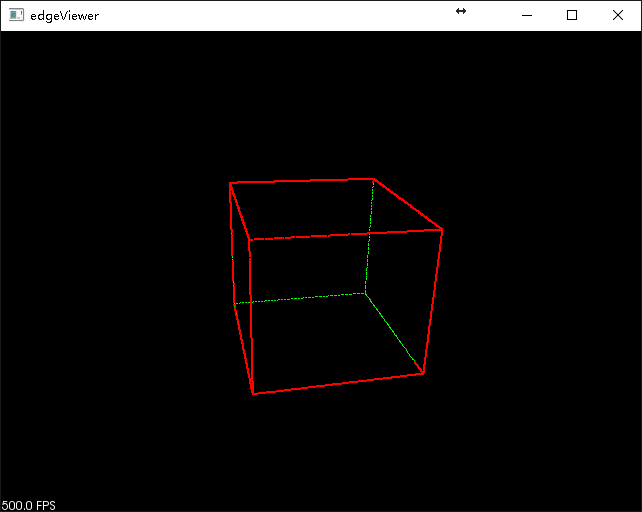
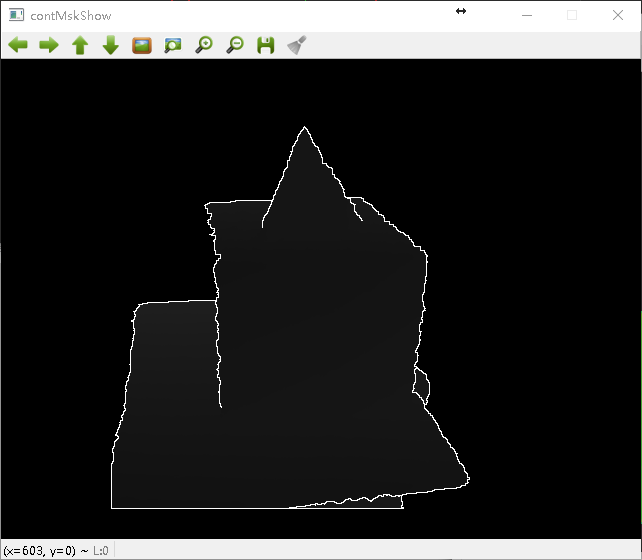
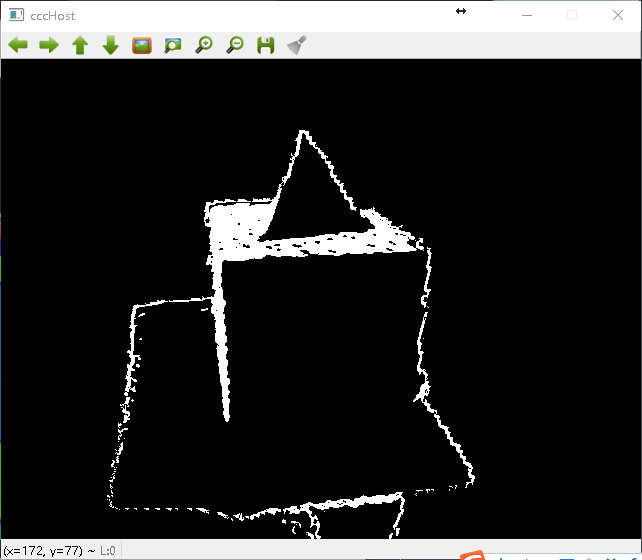
以下图示中，对虚拟立方体轮廓，用红点(pointSize=2)绘制视点中可见轮廓，用绿点(pointSize=1)绘制视点中不可见轮廓。对真实场景中边缘线，以白色线绘制，叠加在原来的深度图（灰度图）上。

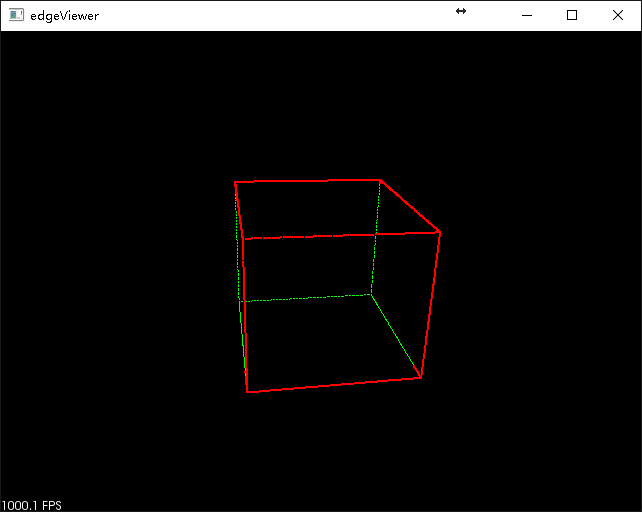
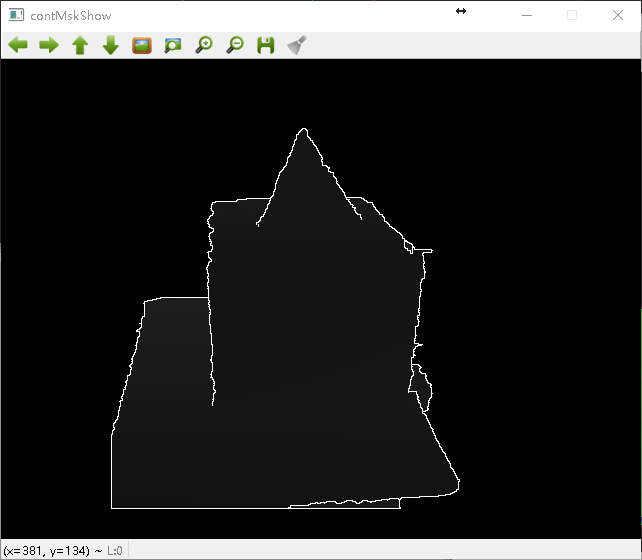
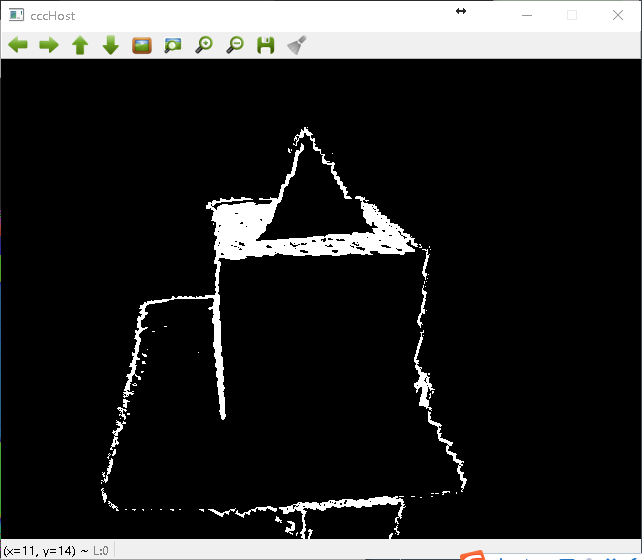
下图中，每一行，左侧图是虚拟立方体轮廓（红色为可见）；中间图白色线框为深度图上，按论文[1]公式(1)边缘检测规则提取的场景边缘；右侧图白色区域为论文[1]边缘对应候选点集（contour correspondence candidates）结果（我们实现），作为中间图的对比。

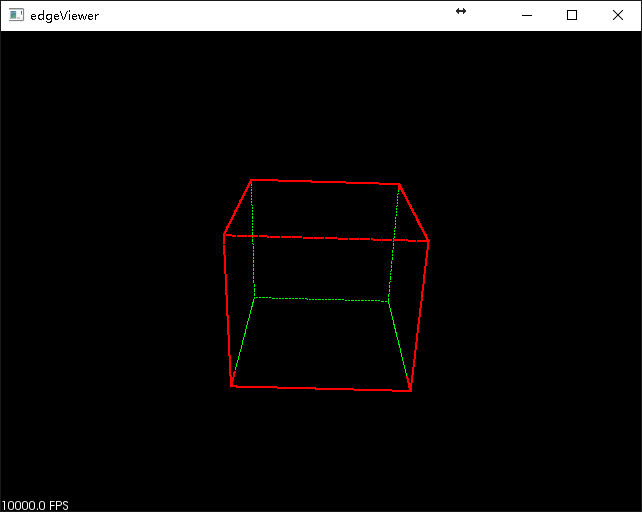
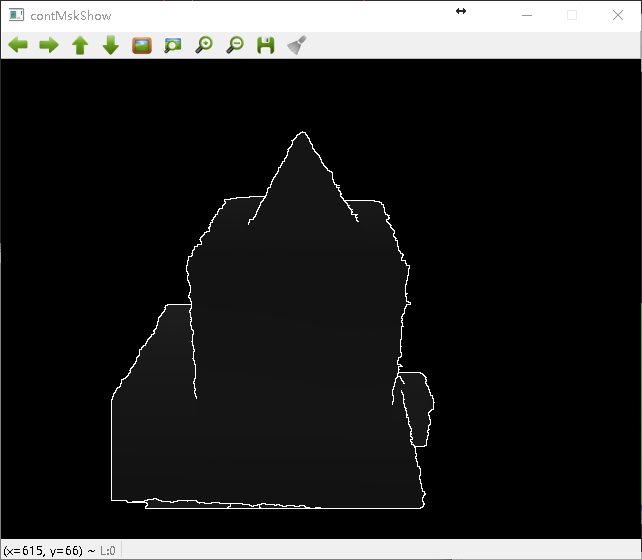
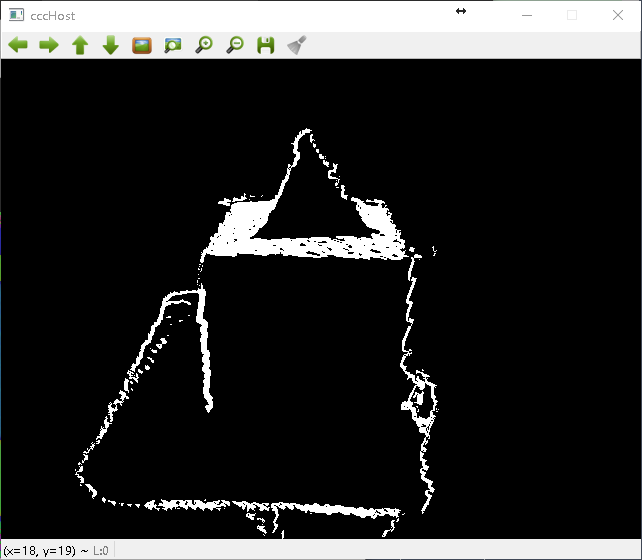
  

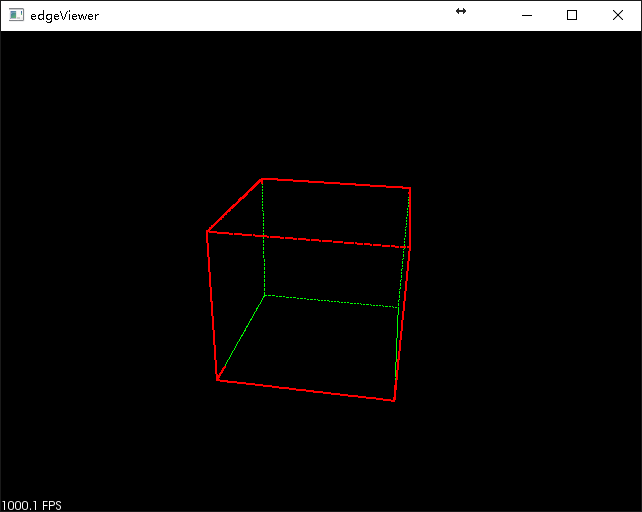
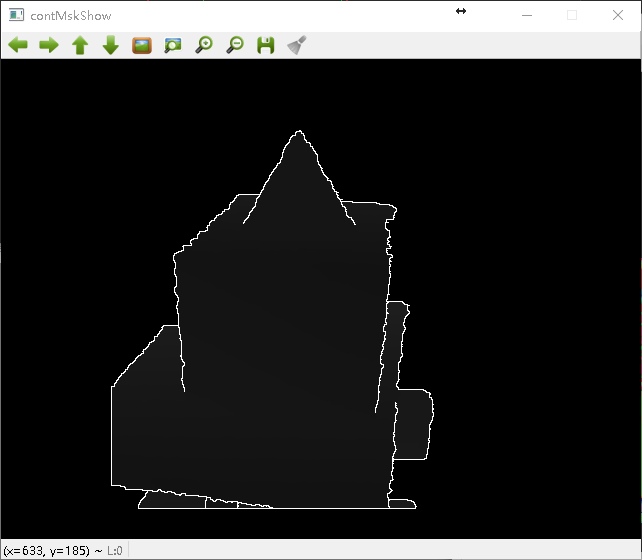
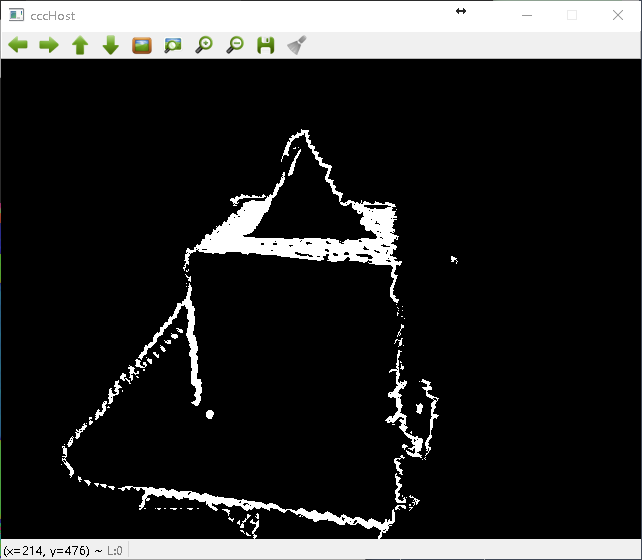
  

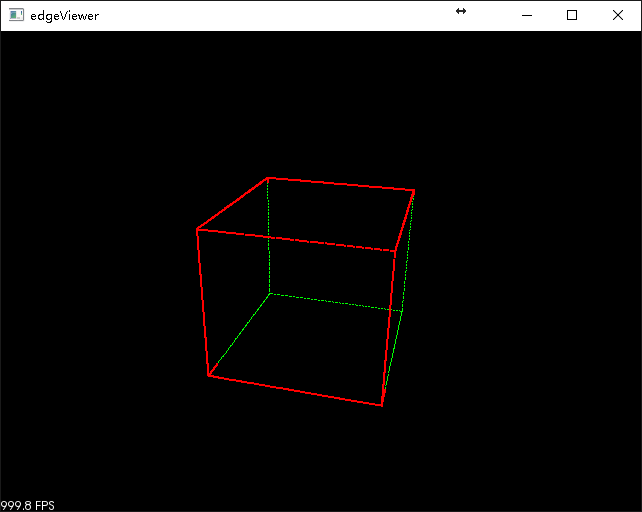
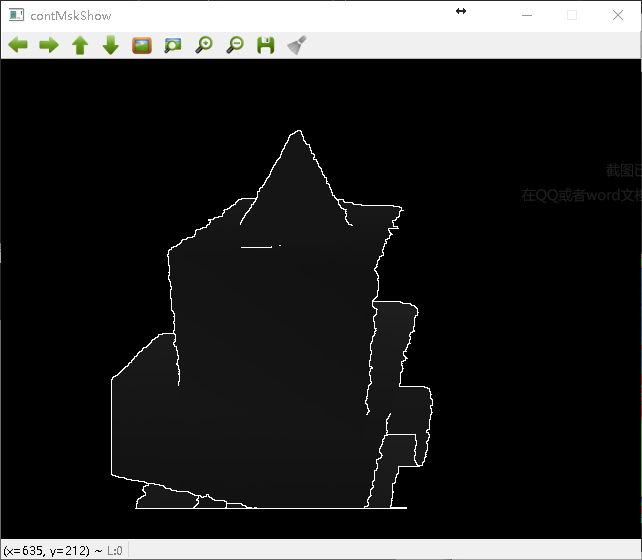
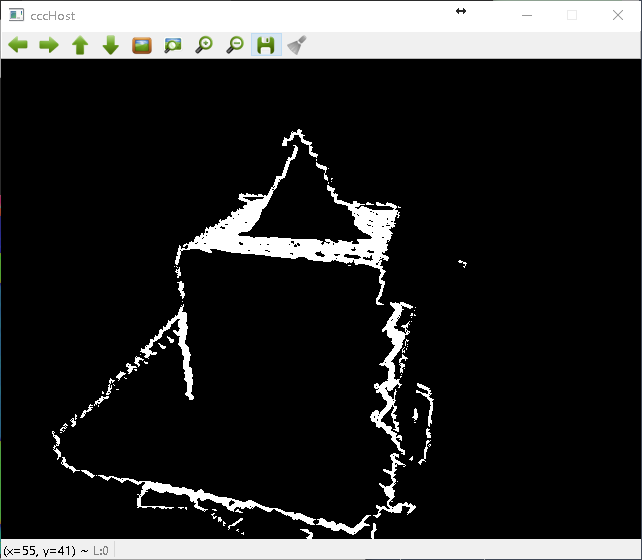
  

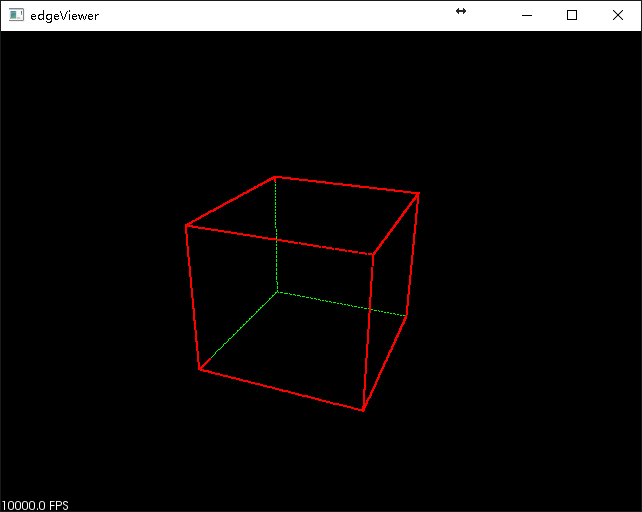
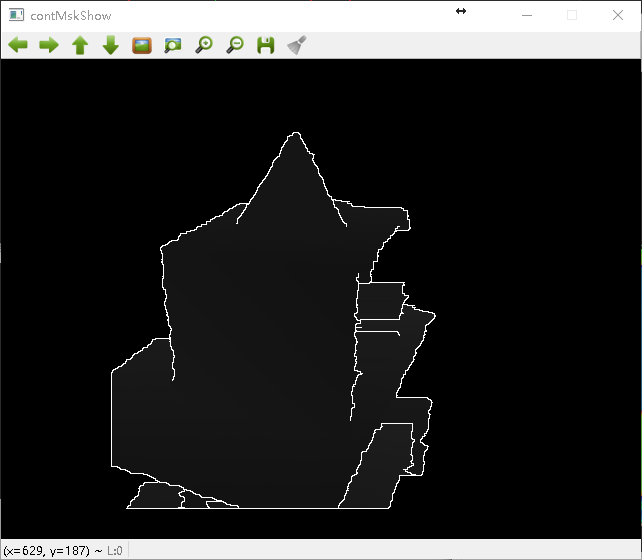
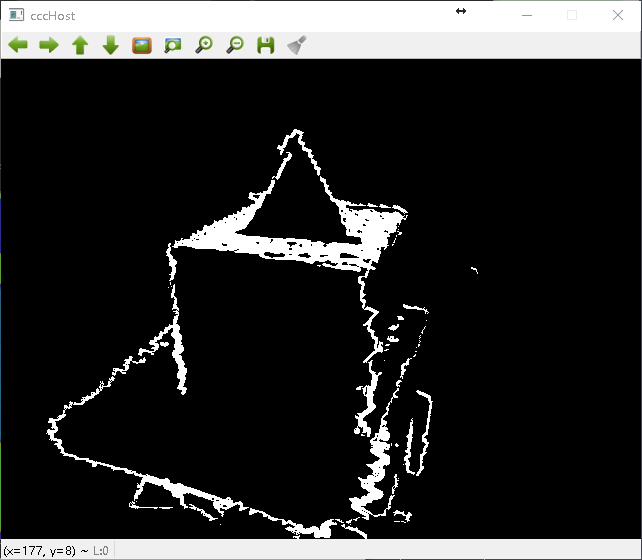
  

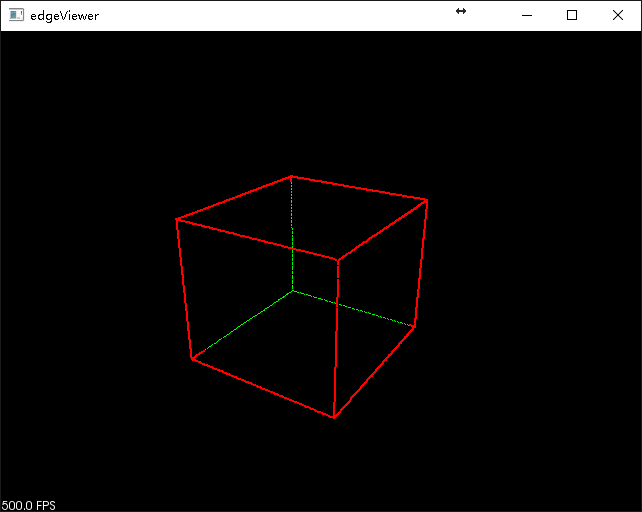
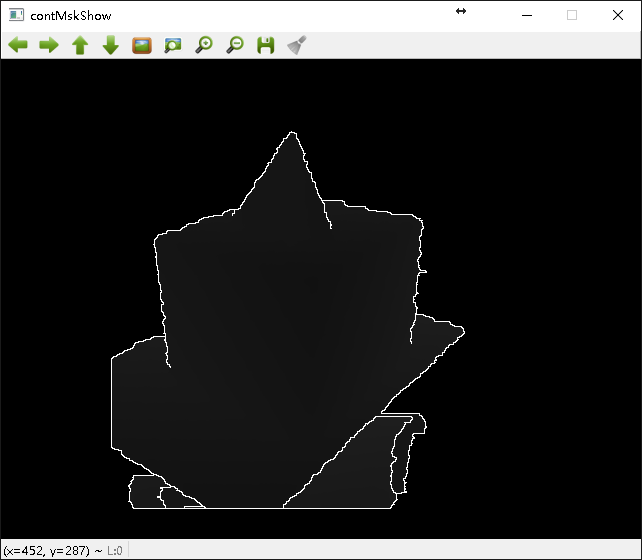
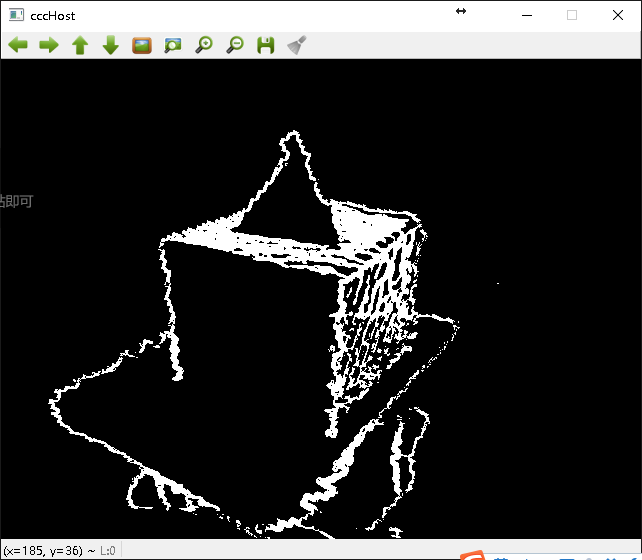
  

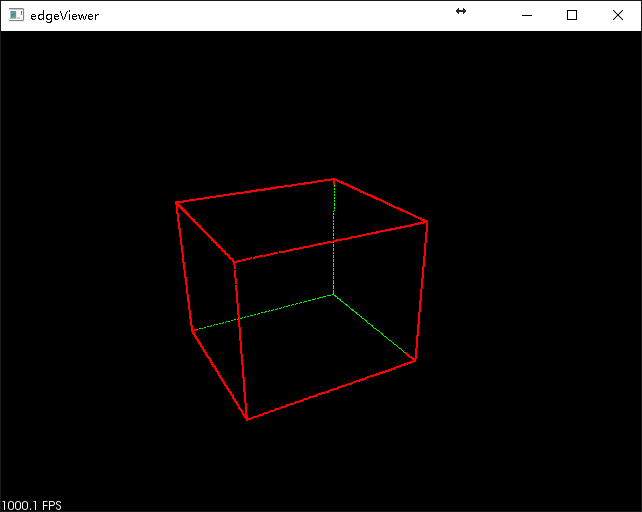
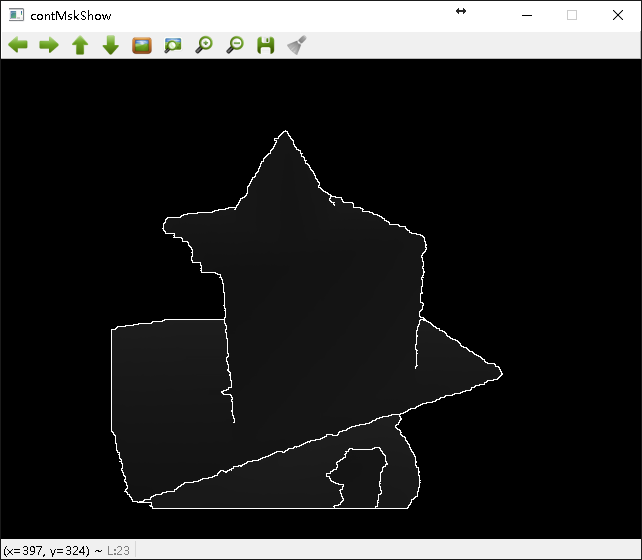
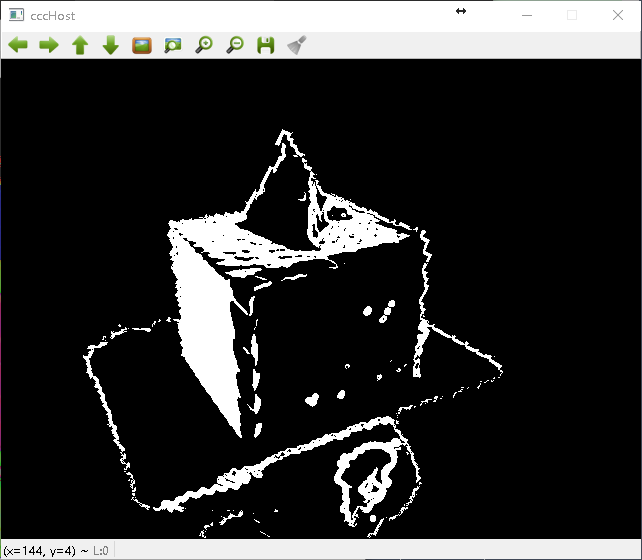
  

## 参考文献

[1] Zhou, Qian-Yi, and Vladlen Koltun. "Depth camera tracking with contour cues." Proceedings of the IEEE Conference on Computer Vision and Pattern Recognition. 2015.