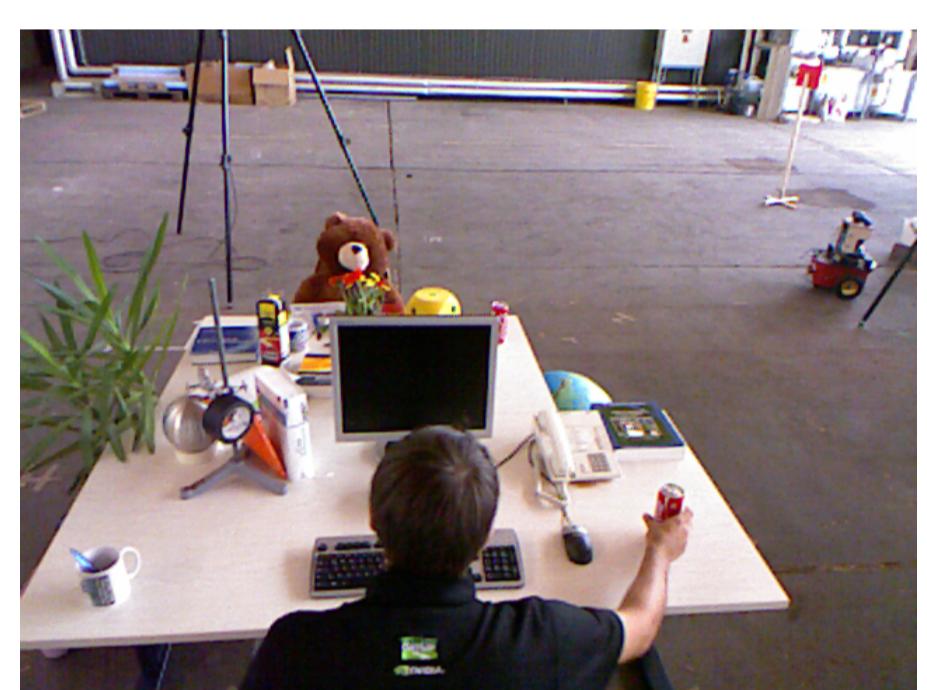
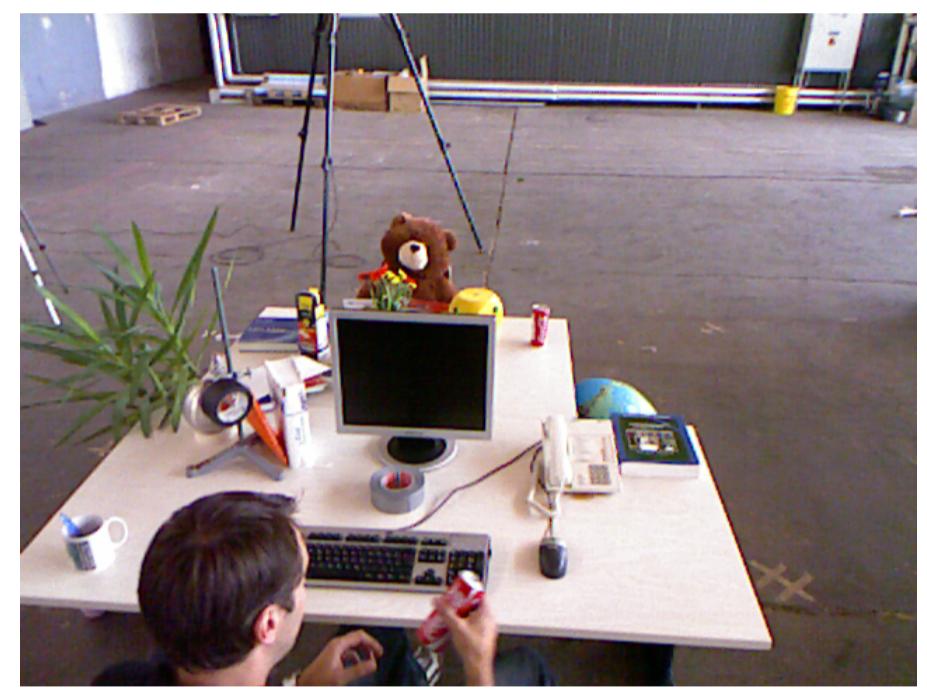
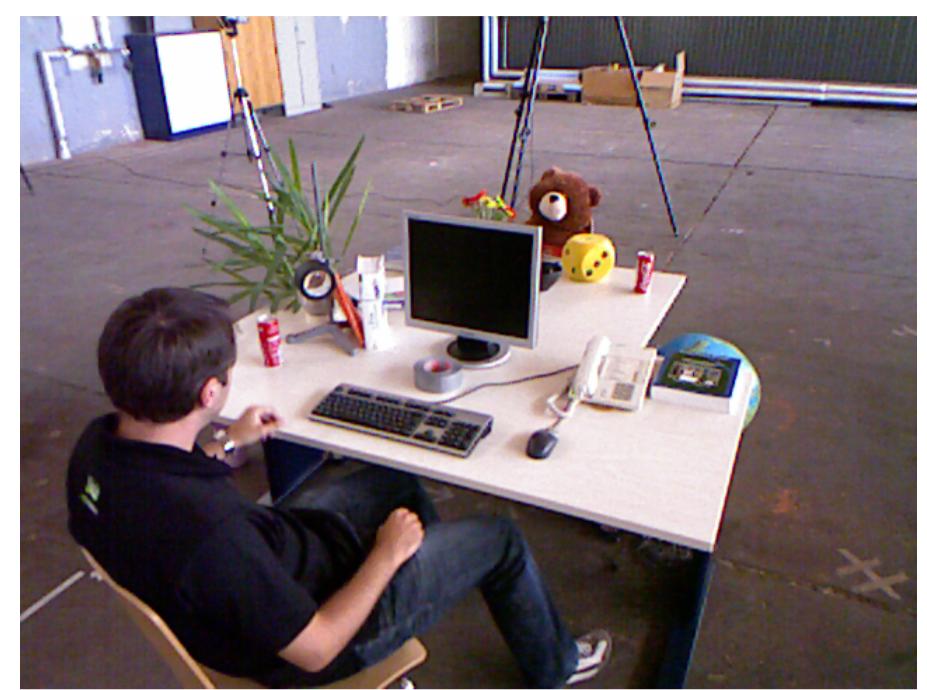


RGB-D sequence



Proposed Pipeline

ORB-SLAM

Dynamic
Object
Detector

Filling the
Holes

Static map of the scene

