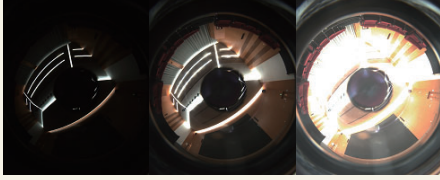
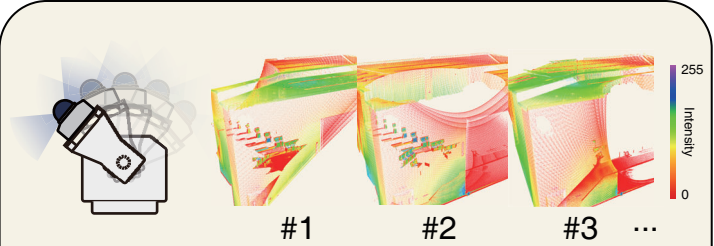


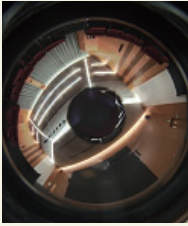
Edge Extraction



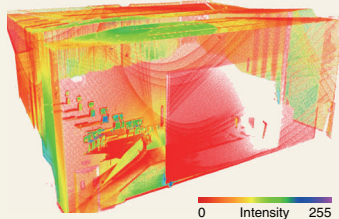
Fisheye images with different exposure times



LiDAR scans from different poses



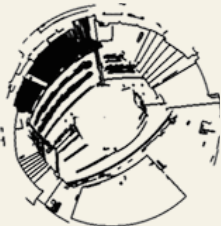
Exposure fusion



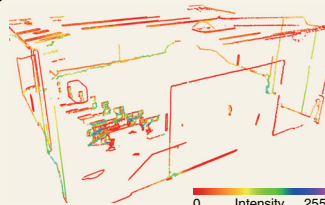
Point cloud registration



Projection by azimuth and pitch angles



Canny edge extraction

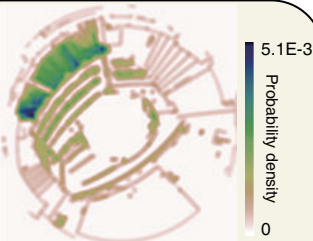


Obtain the original point clouds

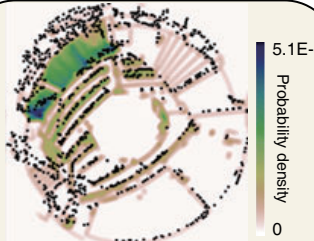


Canny edge extraction

Iterative Optimization



Edge distribution estimation by KDE



Projection and edge probability prediction

$$\hat{\Theta}, \hat{\Delta} = \arg \max_{\Theta, \Delta} \frac{1}{n} \sum_{i=1}^n \|\hat{\mathbf{f}}^{(\mathcal{C})}(\mathbf{p}_i)\|^2$$

Optimization by L-M method

Set bandwidth

Update parameters

Iterate