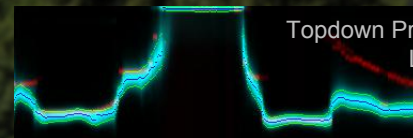


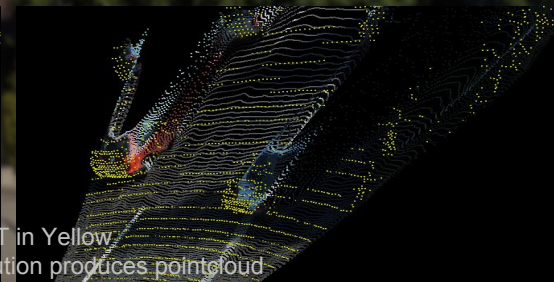
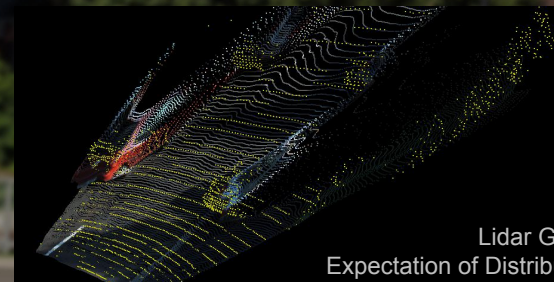
Per Pixel Depth Distribution  
Predicted from Monocular  
RGB

Used to Drive the  
Adaptive Light  
Curtain Laser

Pixel Depth corrected over  
Time from Light Curtain  
Measurements



Topdown Predicted Uncertainty in Blue  
Lidar GT in Red



Lidar GT in Yellow  
Expectation of Distribution produces pointcloud