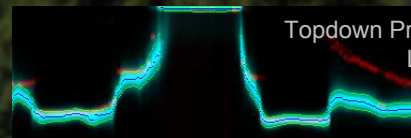


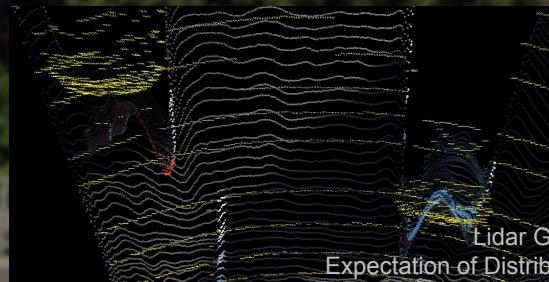
Per Pixel Depth Distribution
Predicted from Monocular
RGB

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

