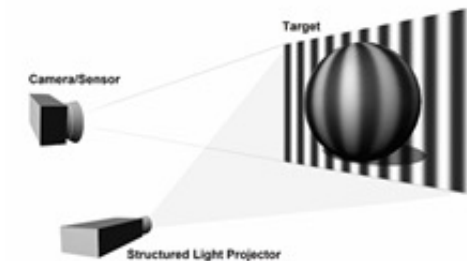


(a) Laser line



Perceptron Scan  
Works V5

Triangulation



(b) Structured light

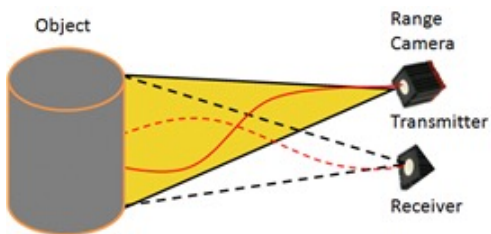


MS Kinect V1  
RGBD camera

Active

3D  
reconstruct

Passive



(c) ToF Camera



MS Kinect V2  
RGBD camera

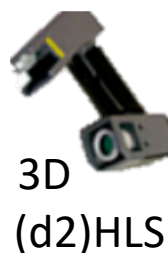
Time of flight (ToF)



(d) Laser scanner (LiDAR)



2D  
(d1)



3D  
(d2)HLS



3D  
(d3)TLS



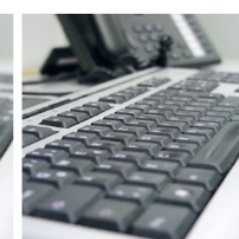
3D  
(d4)ALS



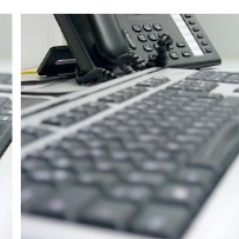
Lytro LF  
RGBD camera



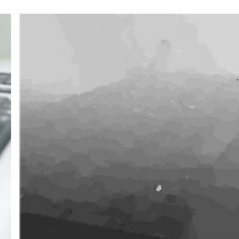
Focal 1



Focal 2



Focal 3

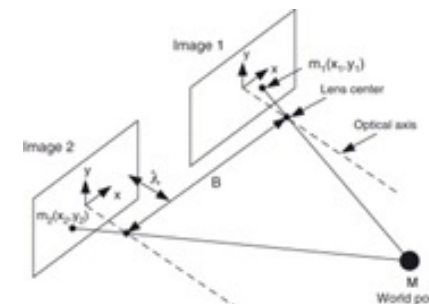


Depth

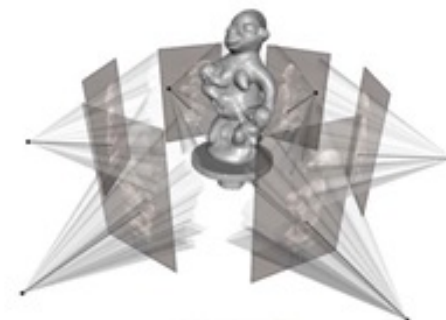
(e) Light field



Intel RealSense  
RGBD camera

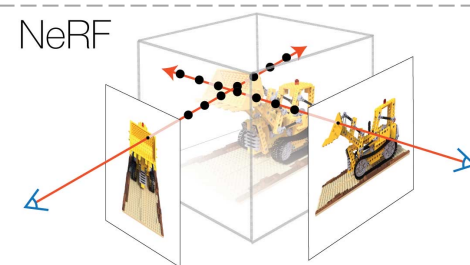


(f) Stereo vision



(g) Structure from motion (SfM)

RGB images  
from different  
perspectives



(h) neural radiance fields (NeRF)