

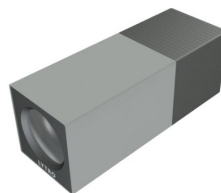
(a) Laser line

Perceptron Scan Works V5

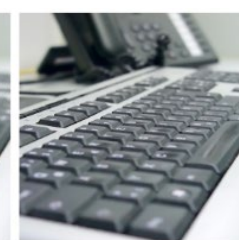


Triangulation

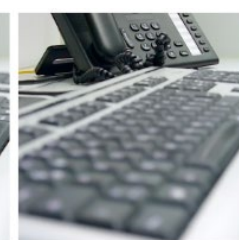
Lytro LF
RGBD camera



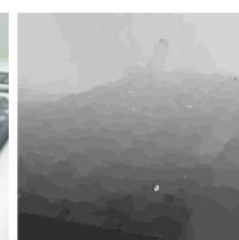
Focal 1



Focal 2

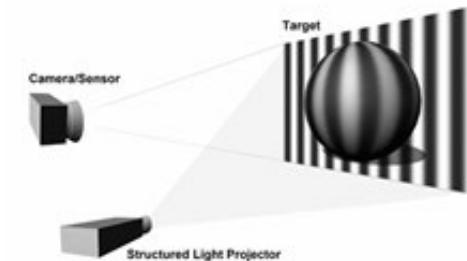


Focal 3



Depth

(e) Light field



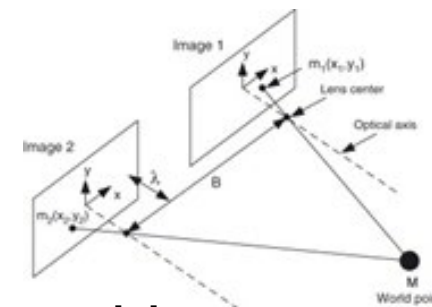
(b) Structured light



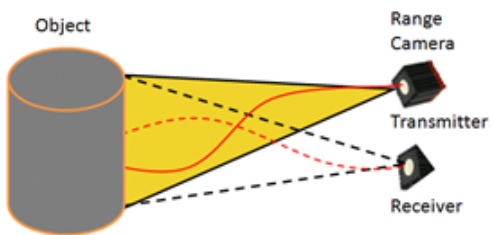
MS Kinect V1
RGBD camera



Intel RealSense
RGBD camera



(f) Stereo vision



(c) ToF Camera



MS Kinect V2
RGBD camera

Active

3D
reconstruct

Passive

Time of flight (ToF)



(d) Laser scanner (LiDAR)



2D
(d1)



3D
(d2)HLS



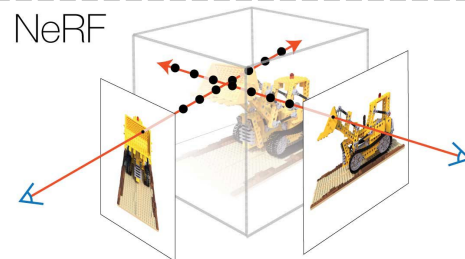
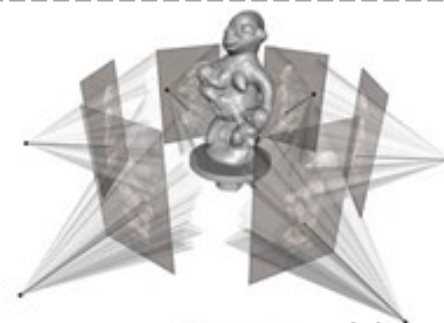
3D
(d3)TLS



3D
(d4)ALS

RGB images
from different
perspectives

(g) Photogrammetry (SfM-MVS)



(h) neural radiance fields (NeRF)