Sec. 3.1 Incremental Reconstruction

Pair 1





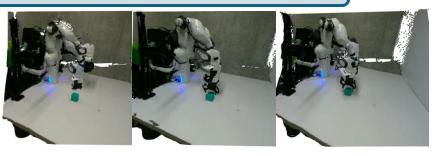
previous frames



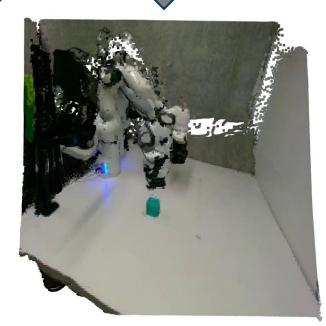


current frames

Input video



Pair 2 Pair 3
Pairwise results



Global pointmap

Sec. 3.2 Robot 2D-3D Correspondence

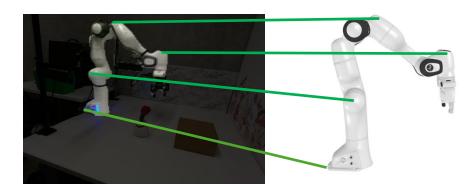
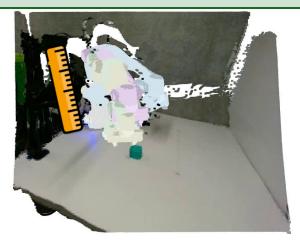


Image & Mask

Robot 3D model

Sec. 3.3 Joint Robot & Scene Optimization



Register robot in the scene

Align scene to metric scale