

images (0..t)

3D points (t)

camera pose (t)

Manifold
reconstruction
from sparse
points

$M_{0..W}^{rec}$

$M_{0..kW}^{rec}$

Photometric
refinement

$M_{0..(k-1)W}^{opt}$

$M_{0..kW}^{merged}$

Mesh merging

current 3D
reconstruction

