

images (0..t)

3D points (t)

camera pose (t)

Manifold
reconstruction
from sparse
points

THREAD 1

M_0^{rec}

$M_{0..t}^{\text{rec}}$

Photometric
refinement

current 3D
reconstruction

$M_{0..t-1}^{\text{opt}}$

$M_{0..t}^{\text{merged}}$

Mesh merging

THREAD 2

