

## Supplementary results

Error comparison of the standard Least-squared (LS), Recursive outlier rejecting (ROR), Selective Observations Rejection (SOR) with the robust methods for 3D point-cloud registration considering the Bunny dataset with conditions similar to the experimental section: 3D Point Cloud Registration in the paper.

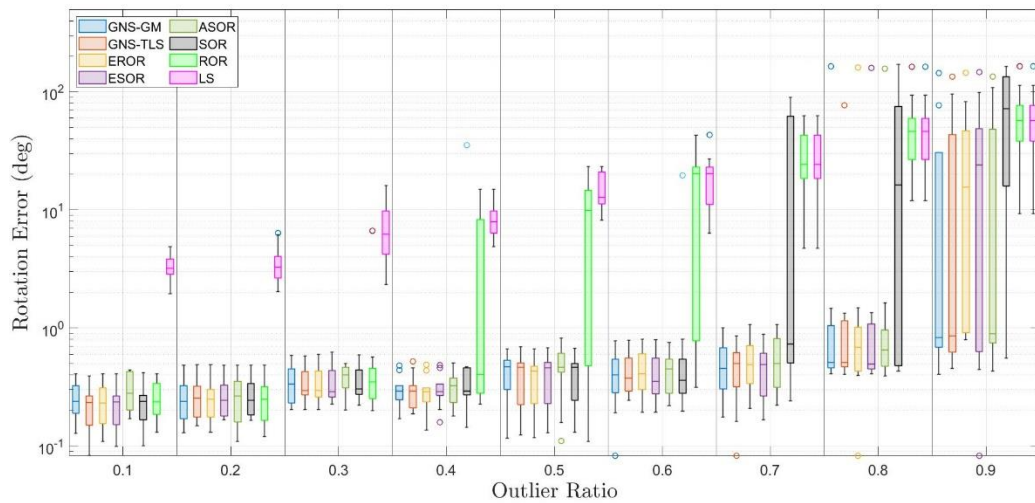


Figure 1a. Rotation error

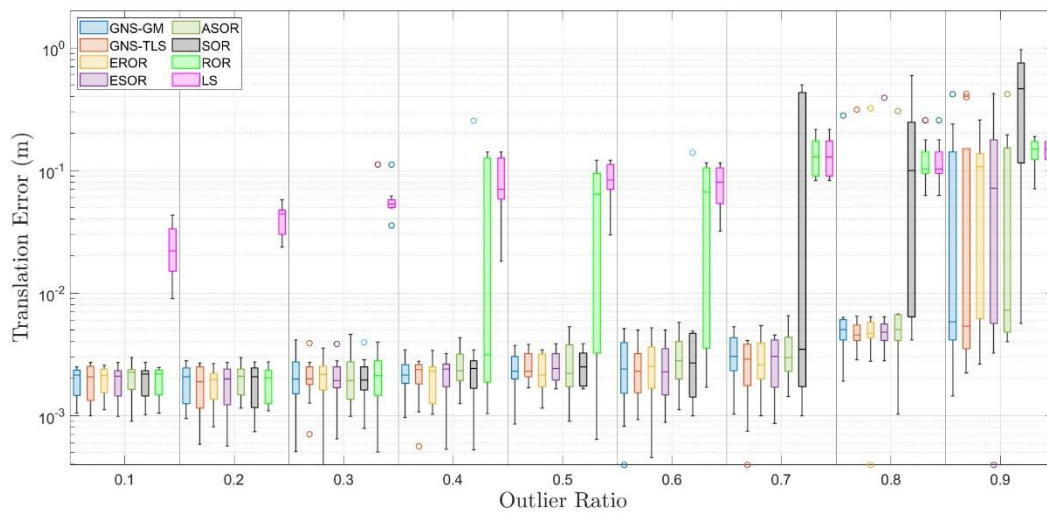
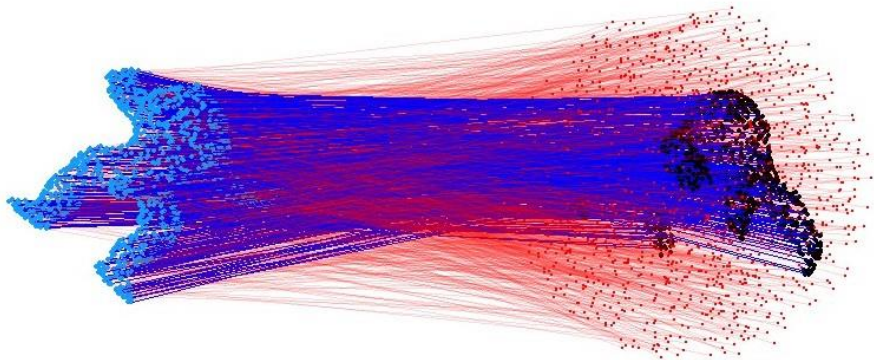


Figure 2b. Translational error

3D point cloud with Armidello dataset with experimental settings similar to the manuscript are given



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Figure 2a . Point clouds with correspondences in 3D point cloud registration for the Armidello dataset

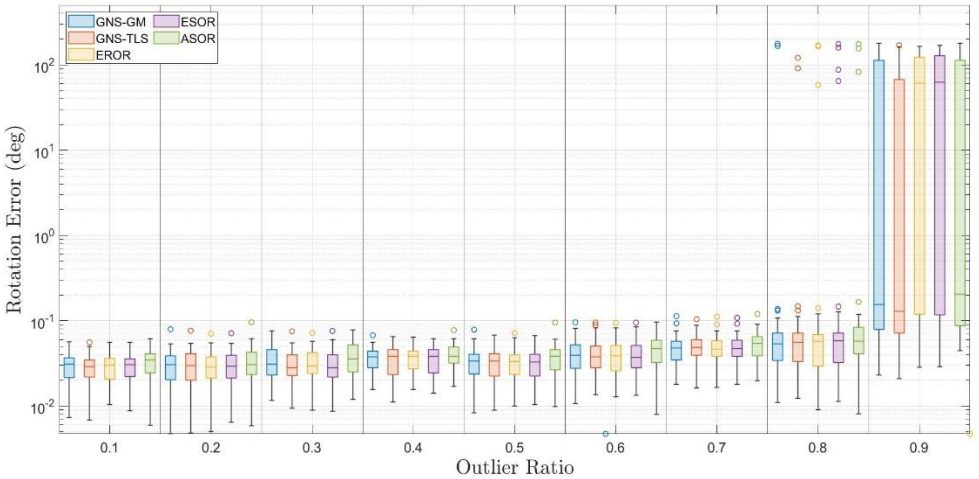


Figure 2b. Rotation error

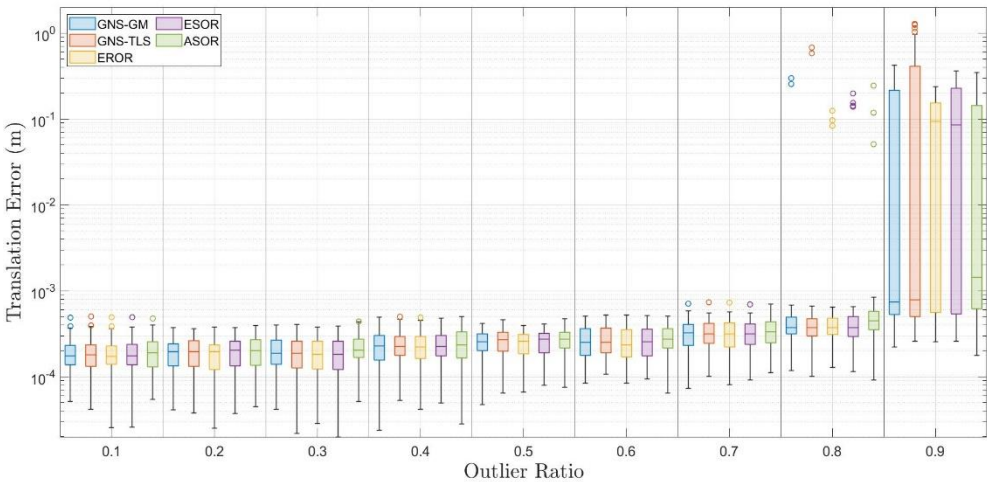


Figure 2c. Translational error

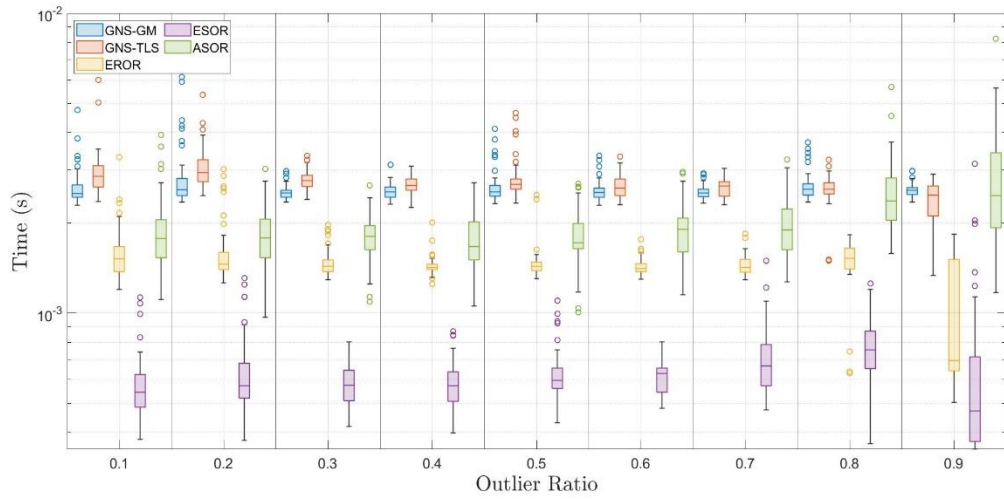


Figure 2d. Computational time

Mesh Registration with Car dataset with experimental settings similar to the manuscript are given as following

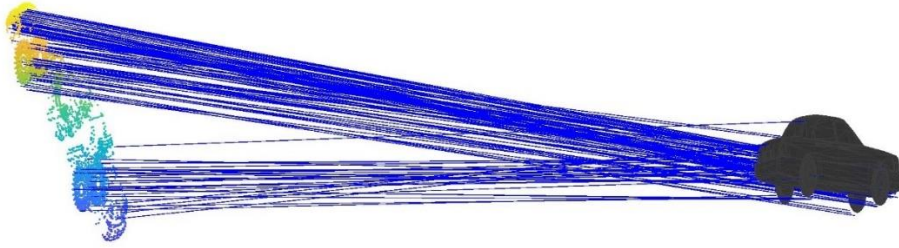


Figure 3a. Mesh and point cloud with correspondences in mesh registration for the car mesh model

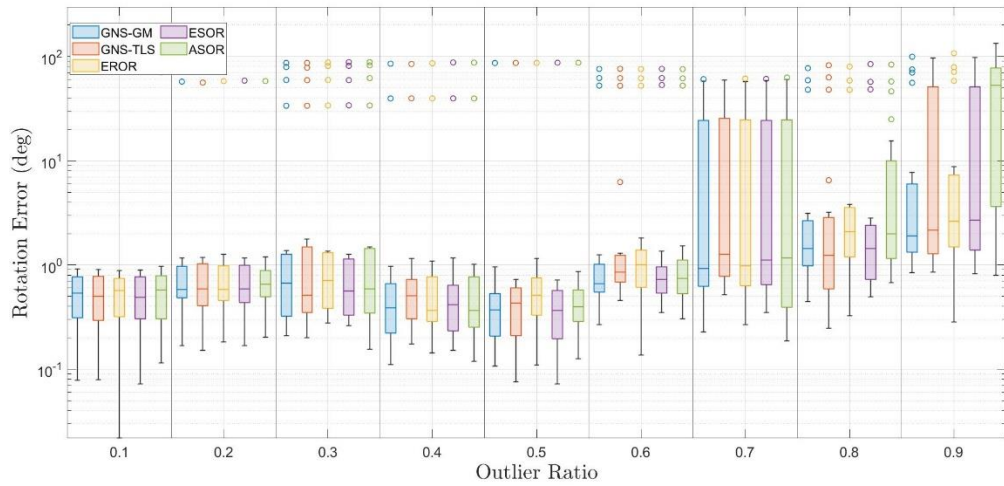


Figure 3b. Rotation error

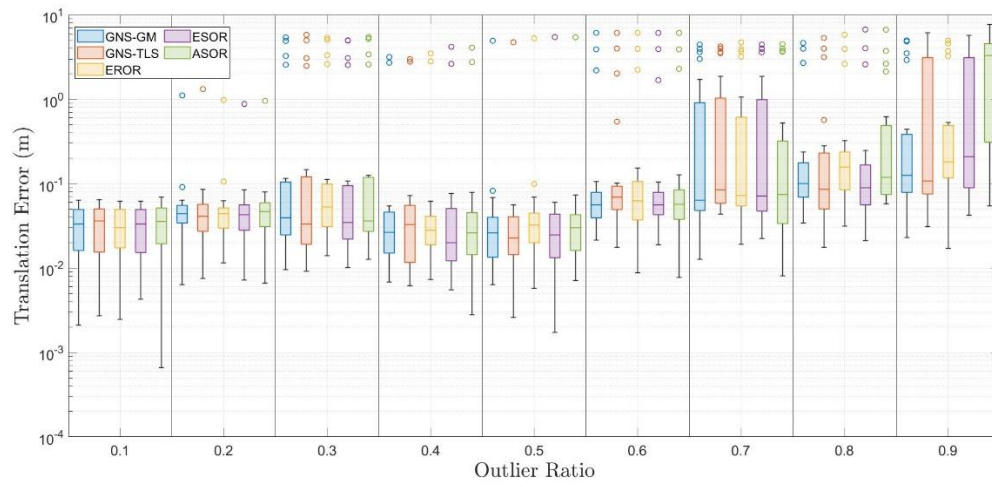


Figure 3c. Translational error

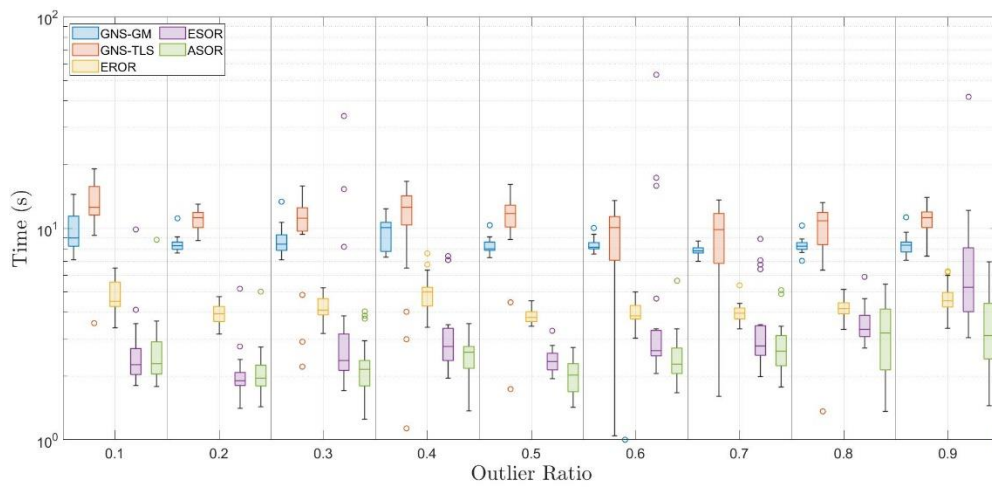


Figure 3d. Computational time