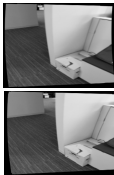**Dense Depth Map**

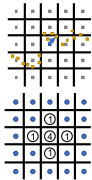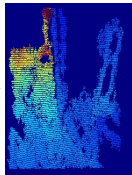Live image → Keyframe selection → Keyframe pool → Selected keyframe → Rectified images → Matching + Invalidation → Planar Bilateral Solver