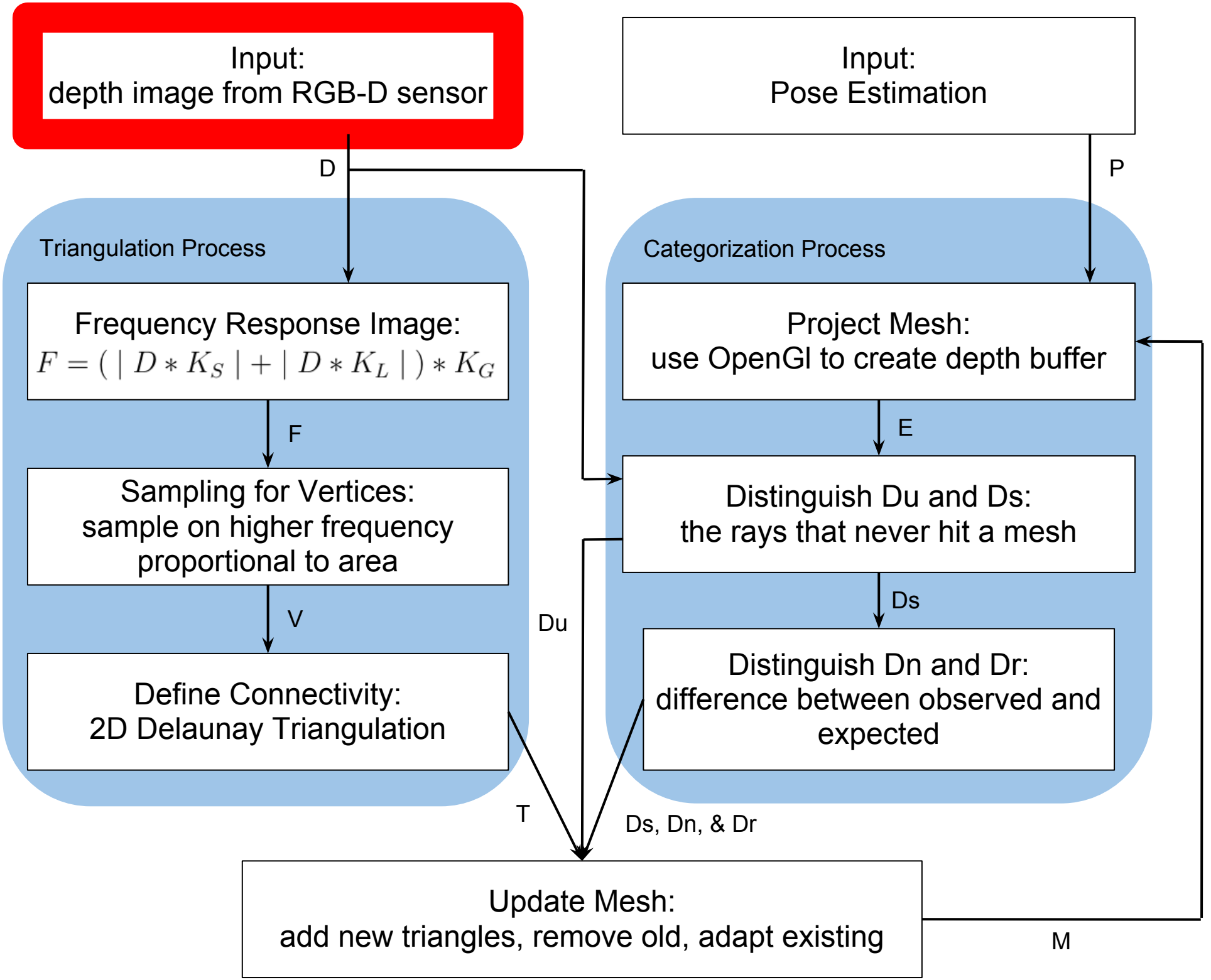
Input:
depth image from RGB-D sensor
Input:
Pose Estimation
D
P
Triangulation Process
Categorization Process
Frequency Response Image:
$F = (\mid D * K_S \mid + \mid D * K_L \mid) * K_G$
Project Mesh:
use OpenGl to create depth buffer
F
E
Sampling for Vertices:
sample on higher frequency
proportional to area
Distinguish Du and Ds:
the rays that never hit a mesh
V
Ds
Du
Define Connectivity:
2D Delaunay Triangulation
Distinguish Dn and Dr:
difference between observed and
expected
T
Ds, Dn, & Dr
Update Mesh:
add new triangles, remove old, adapt existing
M