



Simulated for the Experiments

Input

Depth Image (D) and Pose (P) from sensor.

Classification

P

Generate Expected Depth Image (E)

E

Classify Depth Image (D):

Classification is based on the difference between expected (E) and actual (D).

(D_n) are novel values in the depth image (D).

D_n

Surface Reconstruction:

Novel Surface (S) generated from Novel Values (D_n).
Any surface reconstruction algorithm can be used.

S

Add Novel Surface (S) to Global Mesh (M)

M