Readme:

Part 1:
- Resolution 100 million voxels in a grid of size 4*5*2.5
- Used camera projection matrix to find image coordinates for each voxel and marking as occupied if it is present in all silhouettes
- Stored the voxels in false colored pointcloud

Part 2&3:
- Extracted rgb values from each image for corresponding voxel
- Calculated sum of squared differences wrt mean of intensity.
- If voxel is photo consistent with at least 6 out of 8 images, voxel is marked as surface voxel and is assigned the rgb values of image with minimum SSD.
- Surface voxels are stored in point cloud