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visibility

Visibilities :
 $Q = \{visibility(\mathbf{p}) \mid \mathbf{p} \in P\}$

markov clustering

Visibility clustering :
 $C_Q = \{c_i\}_{i=1}^{|Q|}, c_i \in \mathbb{N}$

label transfer

Room segmentation :
 $room : \mathbb{N}^3 \mapsto \mathbb{N}$
 $room(\mathbf{v}) = c, c \in C_Q, \mathbf{v} \in \mathcal{V}$

label propagation

Propagated room segmentation :
 $room^{(t)} : \mathbb{N}^3 \mapsto \mathbb{N}$
 $room^{(t)}(\mathbf{v}) = c, c \in C_Q, \mathbf{v} \in \mathcal{V}$

topometric map

Topometric map :
 $\mathcal{T} = (N, E), N \in \mathcal{R}, N \subset \mathcal{V}$