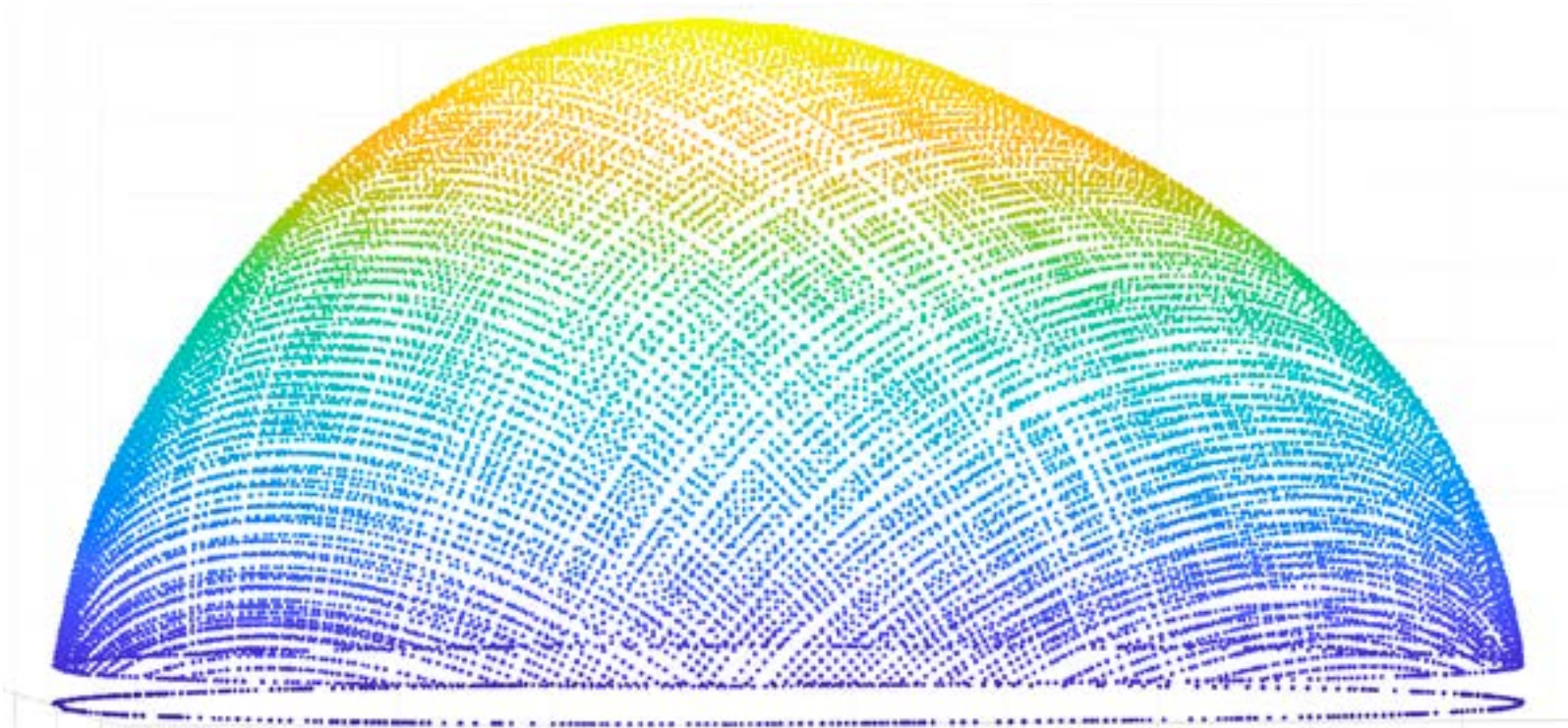# Algorithm Development: Point Cloud Registration

Fixed Point Cloud = Mesh-derived Point Cloud

Moving Point Cloud = Ultrasound-derived Point Cloud

Fixed Point Cloud

Moving Point Cloud

ICP Registration

Match points between moving and fixed point clouds

Remove incorrect matches - Outlier Filter

Recover rotation and translation - Minimize Error

Check if algorithm stops

Alignment Transformation

The MathWorks, Inc. (2014-2021)