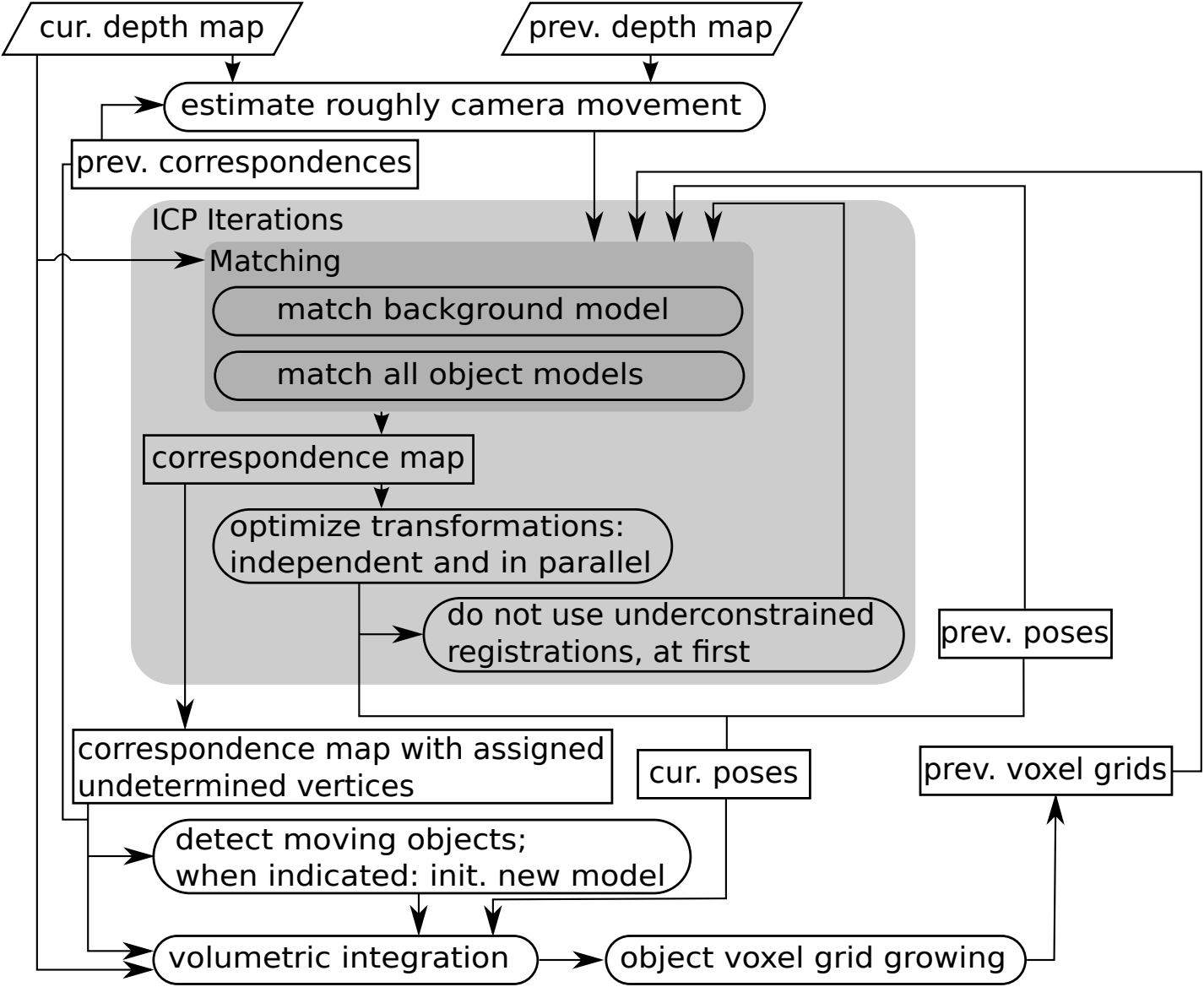
cur. depth map
prev. depth map
estimate roughly camera movement
prev. correspondences
ICP Iterations
Matching
match background model
match all object models
correspondence map
optimize transformations:
independent and in parallel
do not use underconstrained
registrations, at first
prev. poses
correspondence map with assigned
undetermined vertices
cur. poses
prev. voxel grids
detect moving objects;
when indicated: init. new model
volumetric integration
object voxel grid growing