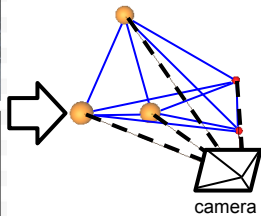
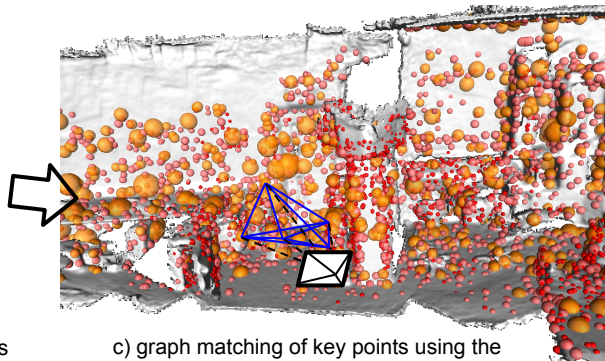




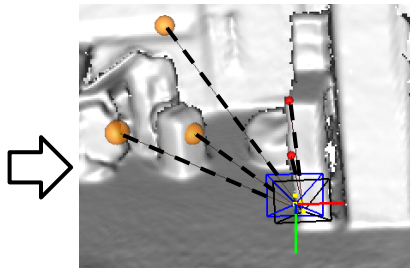
a) input RGBD frame



b) extracting key points



c) graph matching of key points using the pairwise geometry



d) ICP pose refinement