

Supplementary Document for *HeteroFusion: Dense Scene Reconstruction Integrating Multi-sensors*



This supplementary material provides detailed visual results for qualitative comparisons. These abbreviations for algorithms and scenes are consistent with the original text.

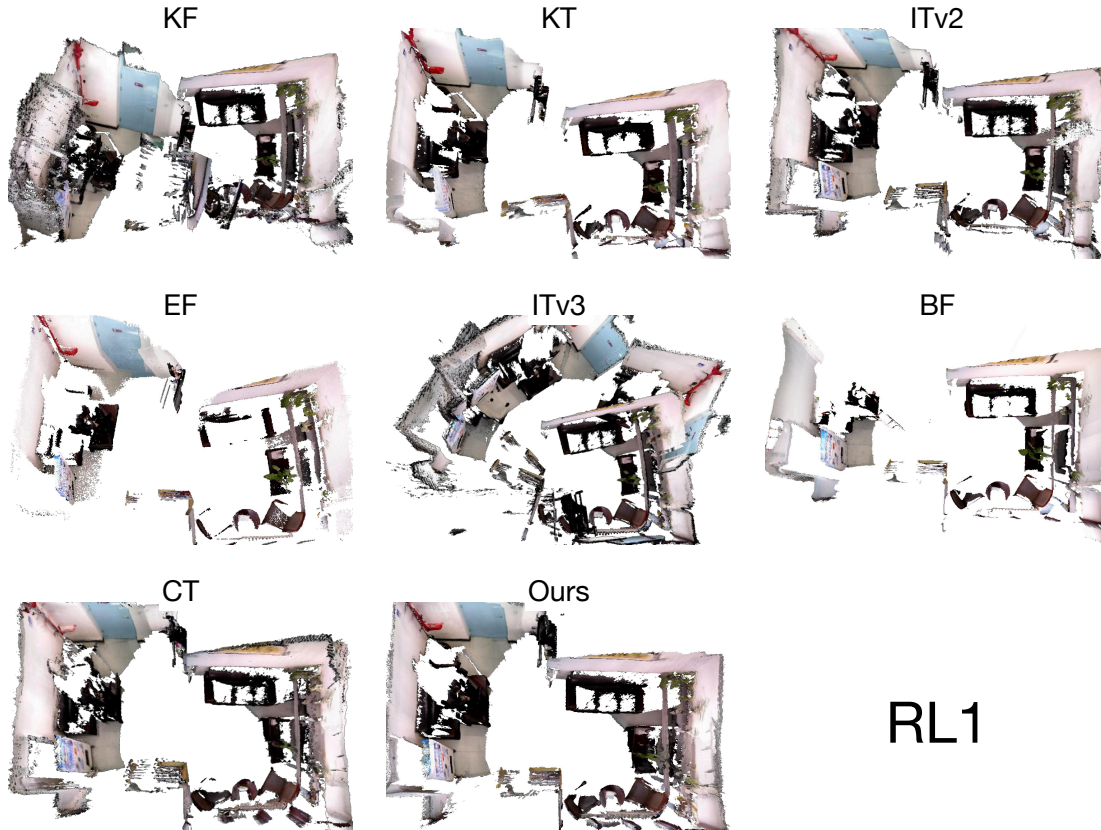
We also provide a supplementary video for comparing the reconstruction progress between ITv3, CT, and ours, where both the submap (first-person) view and the global view are synchronously shown. For CT, since it is not designed for dense reconstruction, we first generate the trajectories of these scans with default parameters and use these trajectories for integrating RGBD frames.

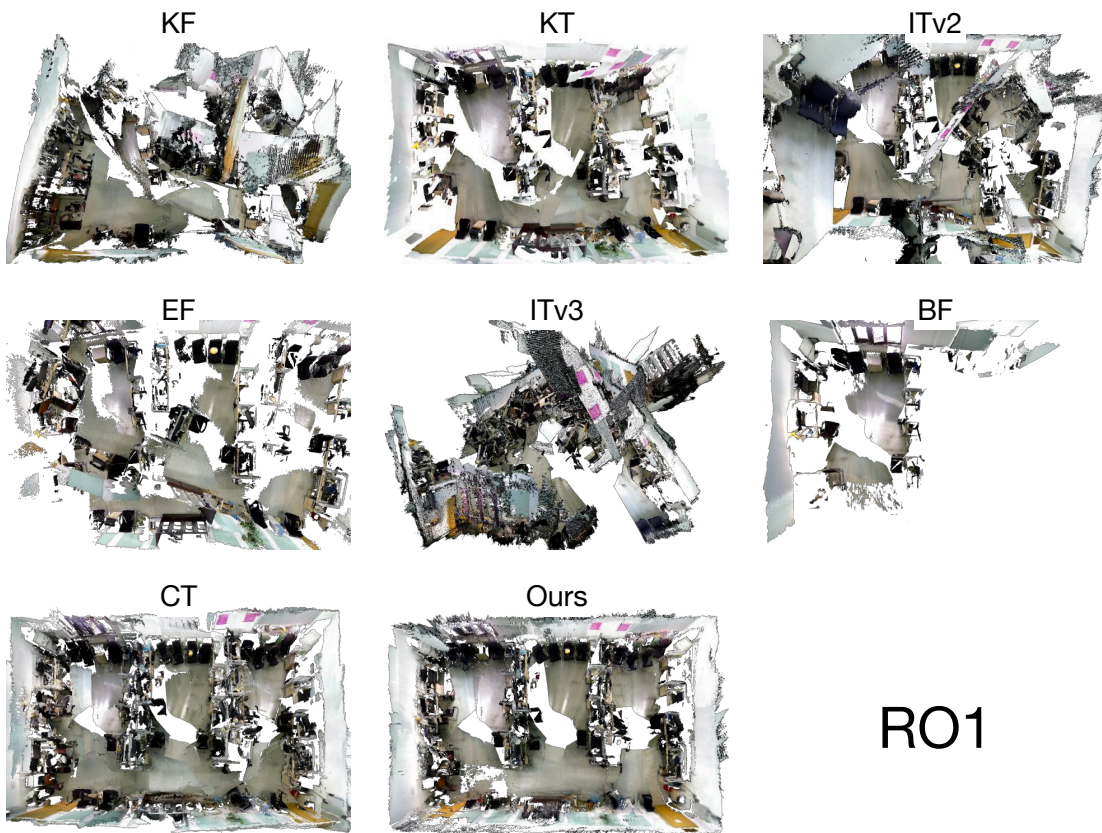
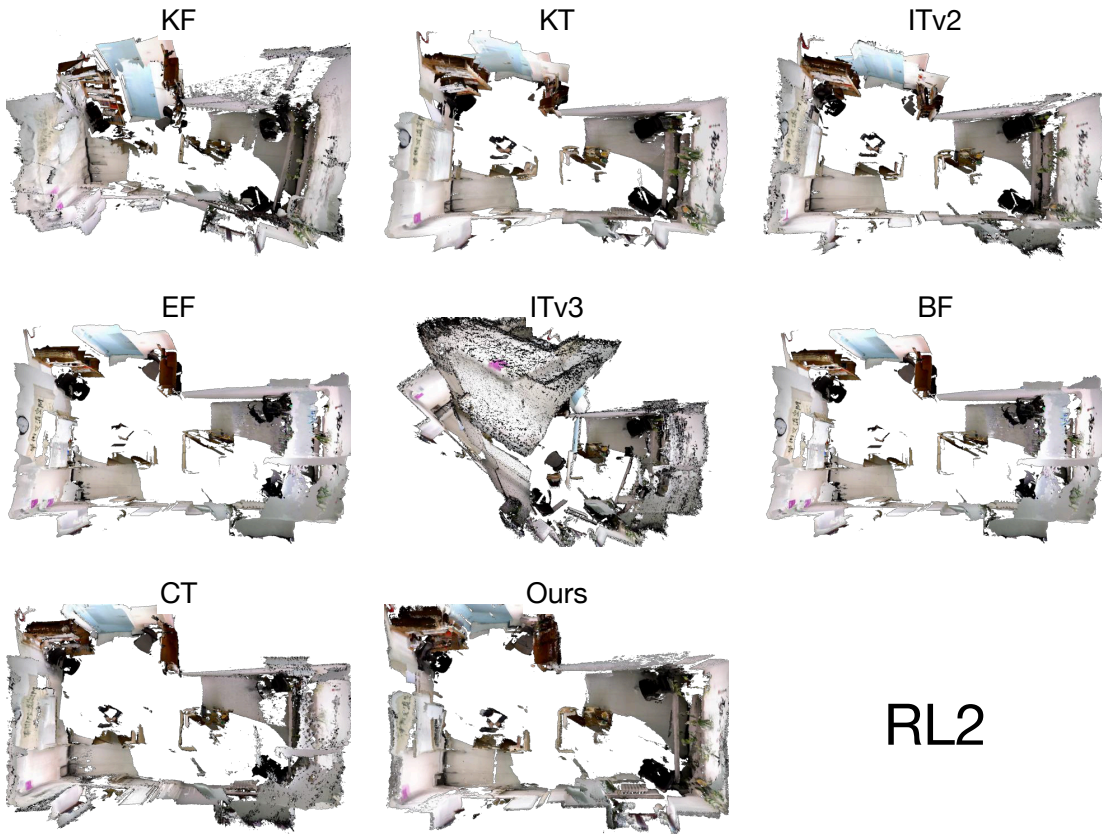
KF	KT	ITv2	EF	ITv3	BF	CT	Ours
KinectFusion	Kintinuuous	InfiniTAM v2	ElasticFusion	InfiniTAM v3	BundleFusion	Cartographer	Ours

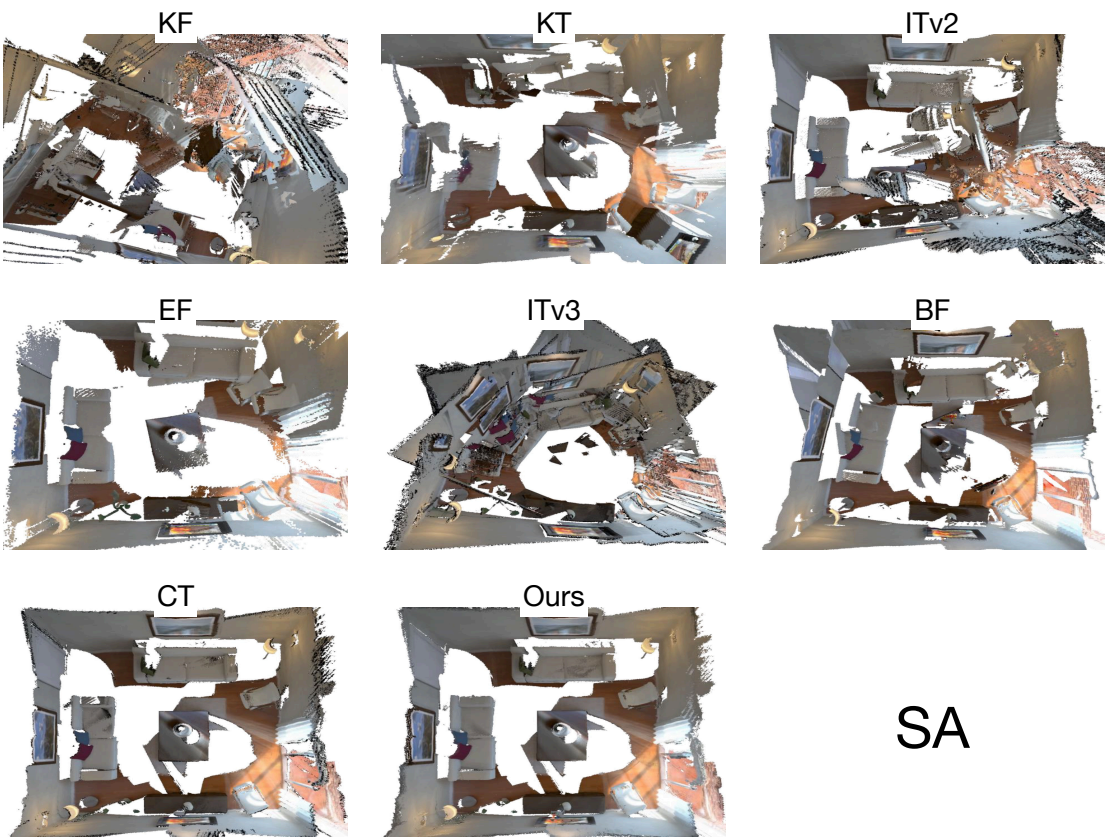
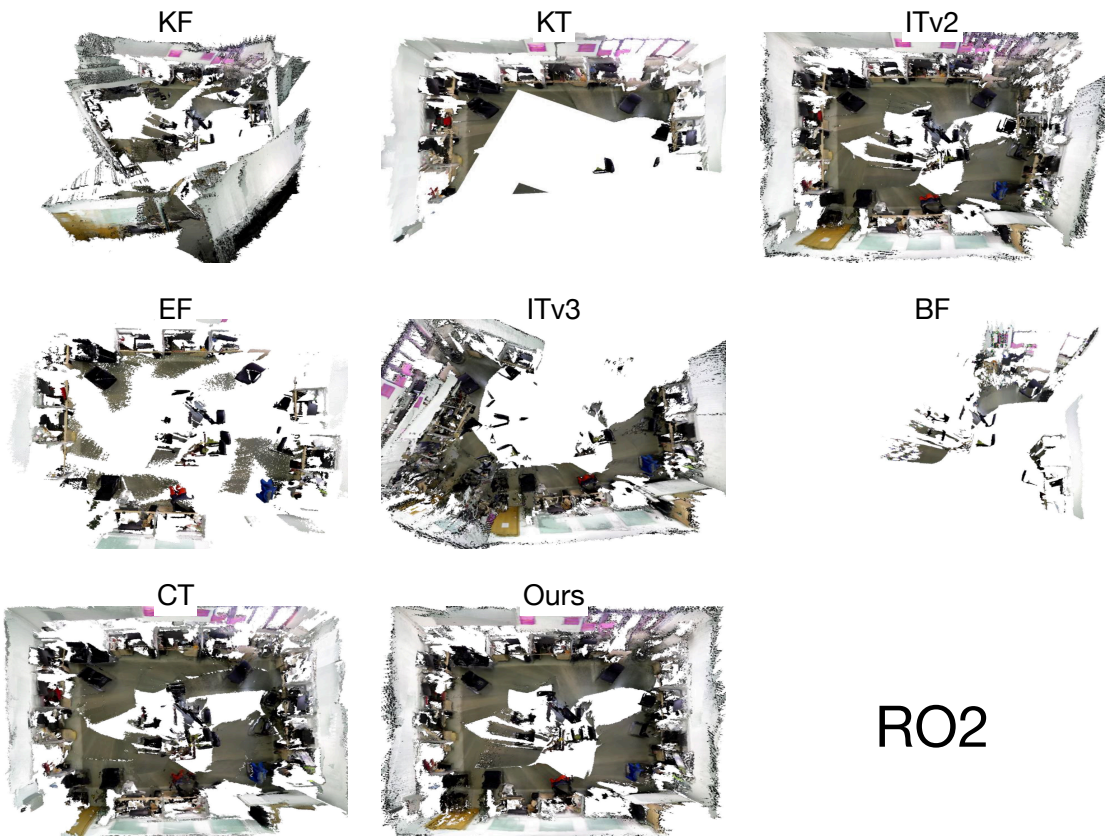
Table 1

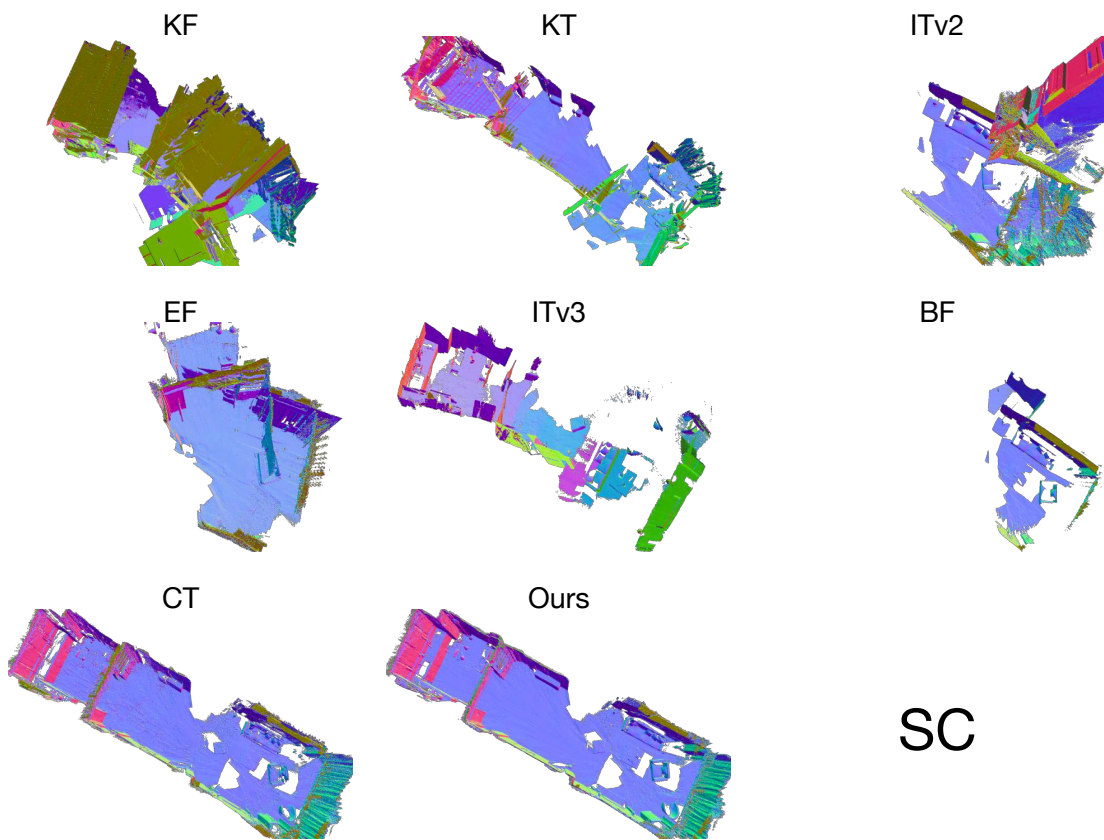
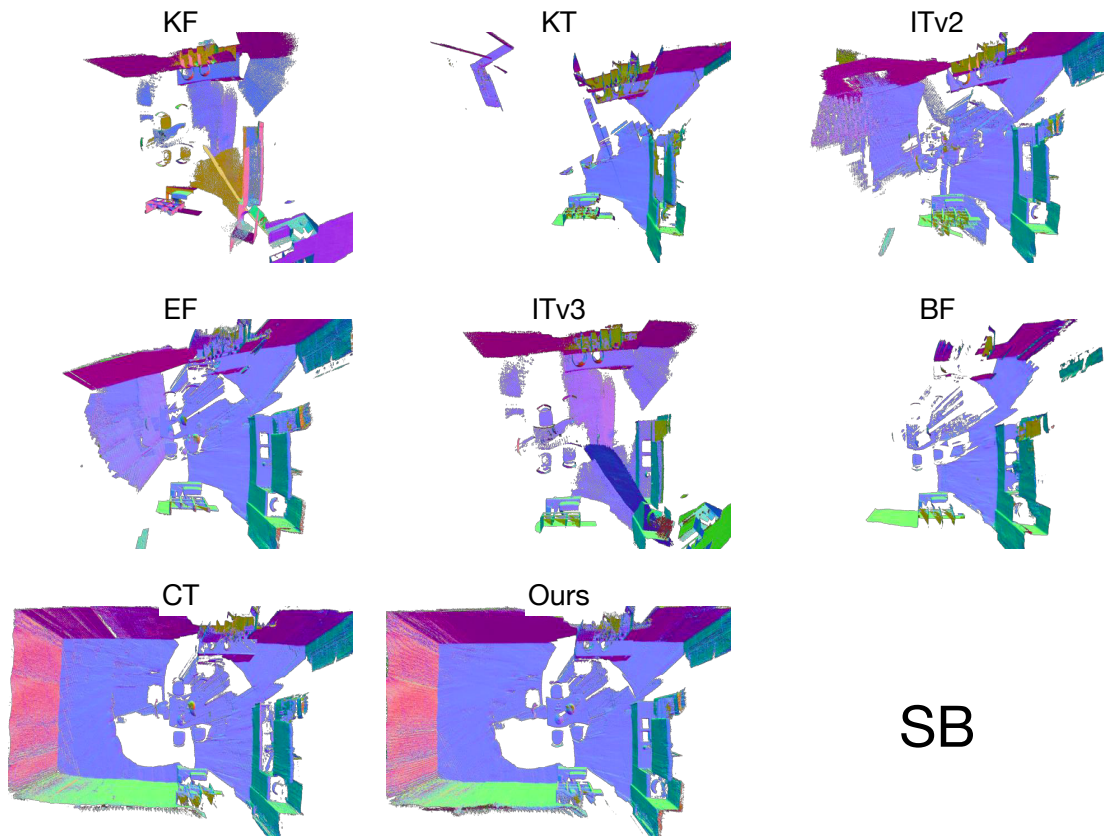
Abbreviations in this document, which are consistent with the paper.

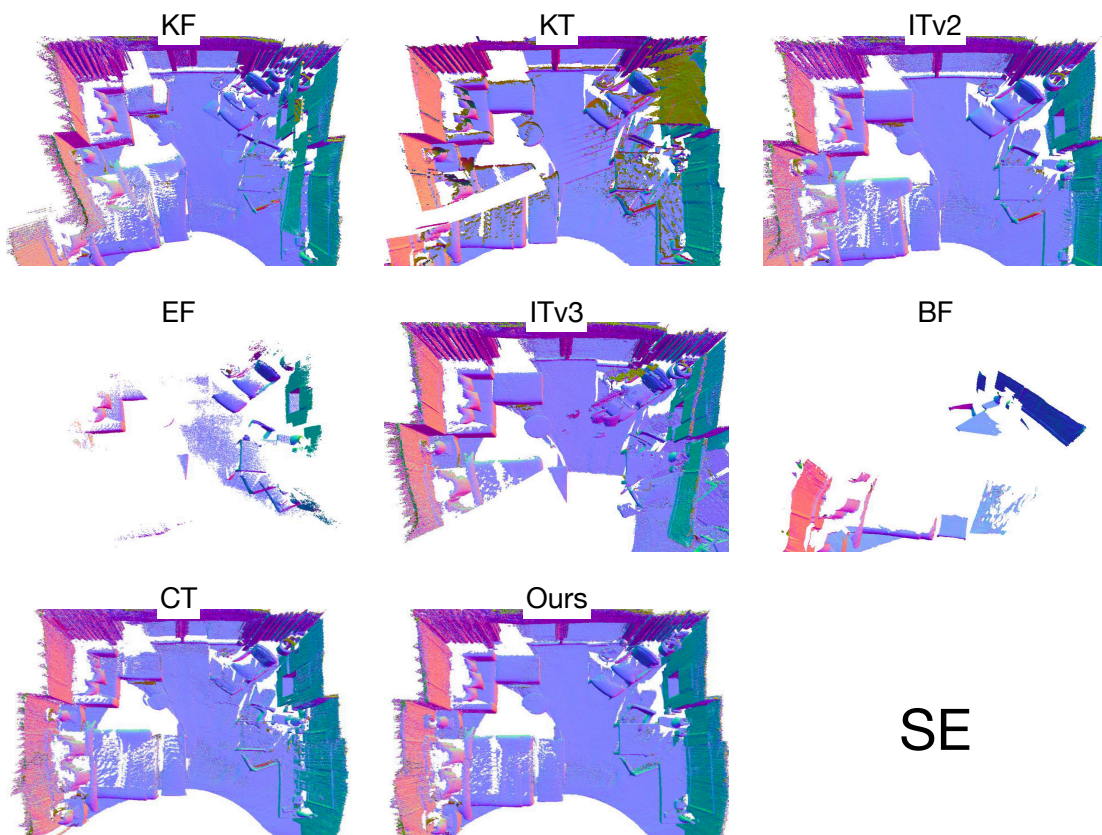
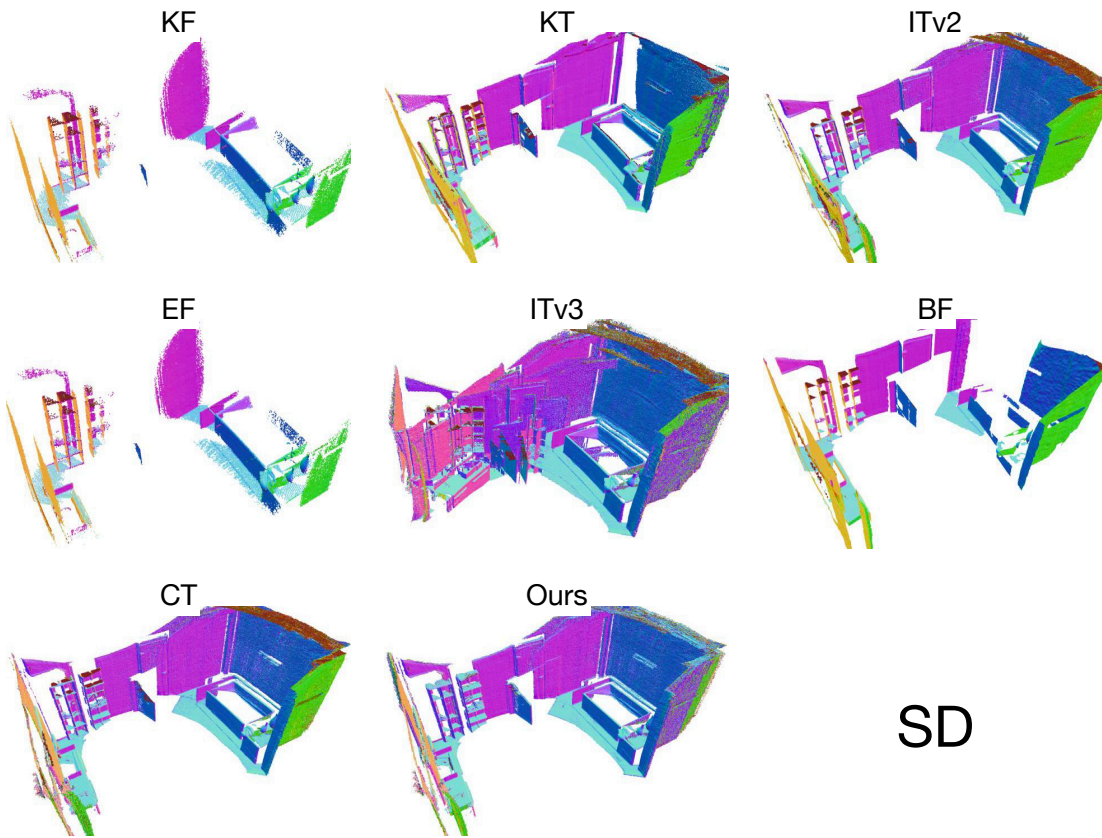
DETAILED COMPARISONS OF FIGURE 8 (PAGES 1-6) AND FIGURE 9 (PAGES 7-12) IN THE PAPER.

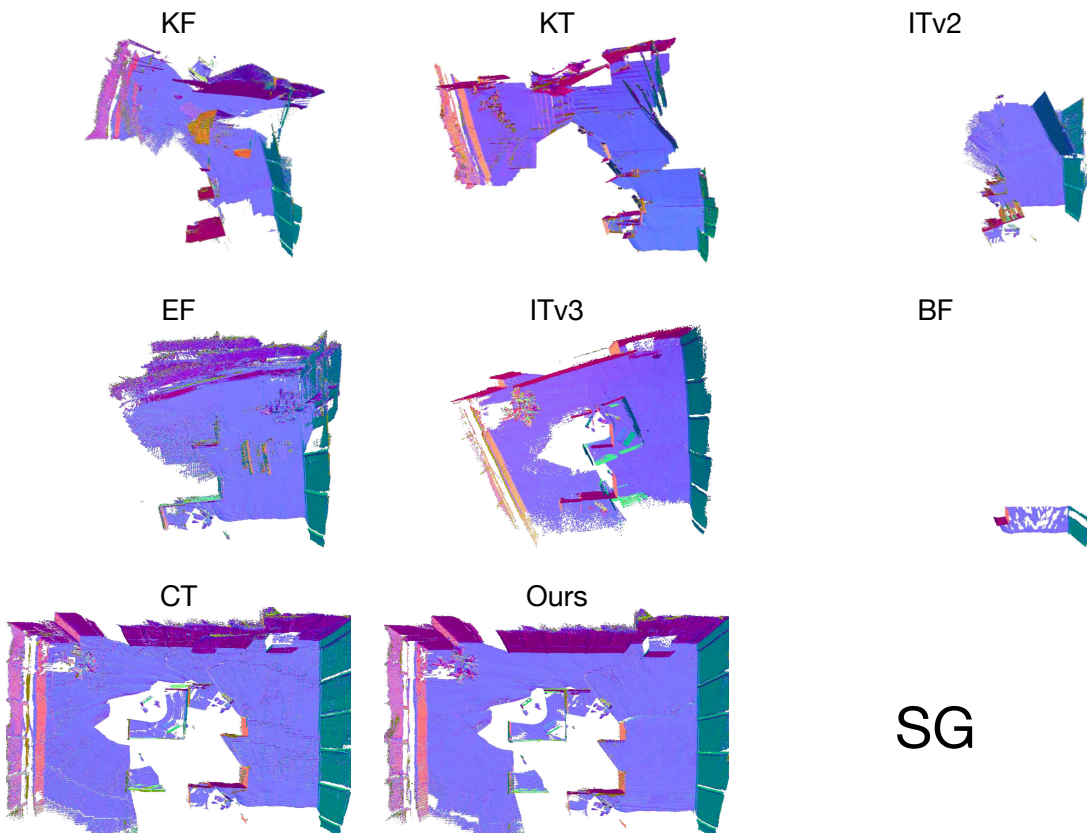
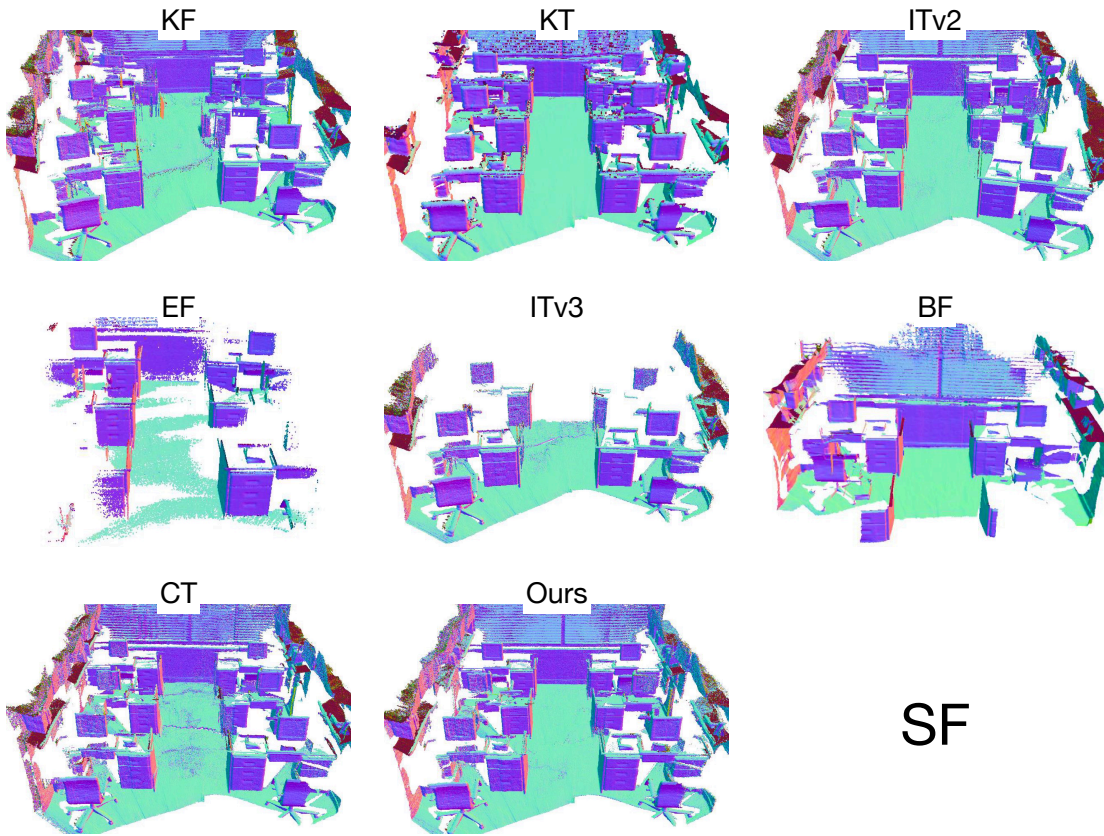












RL1

CT



Ours



RL2

CT



Ours



R01

CT



Ours



R02

CT



Ours

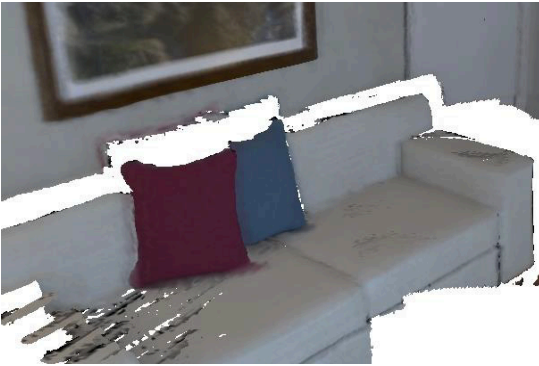


SA

CT

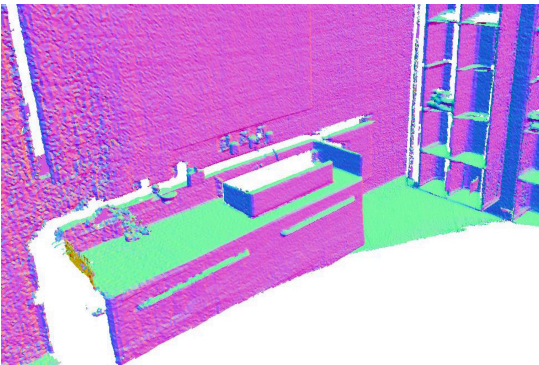


Ours

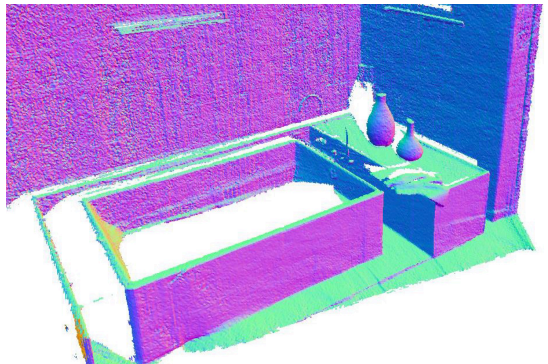
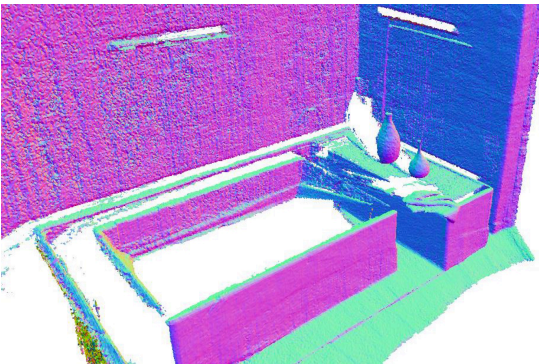
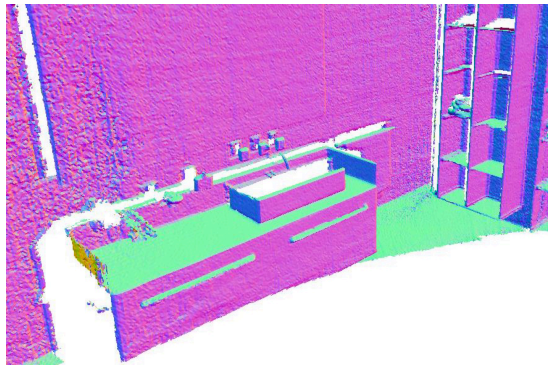


SB

CT



Ours

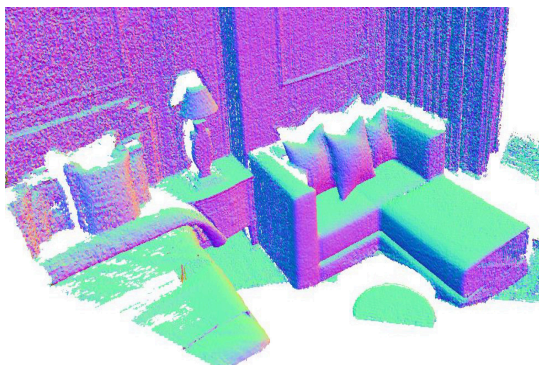


SC

CT



Ours

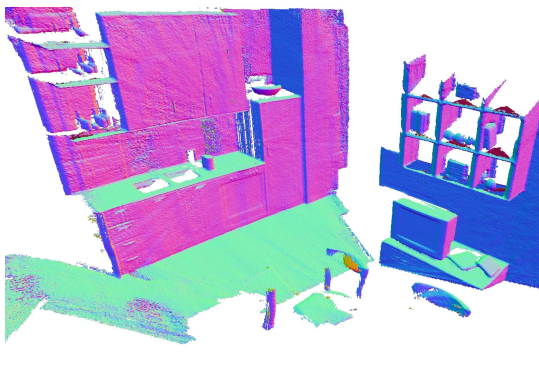
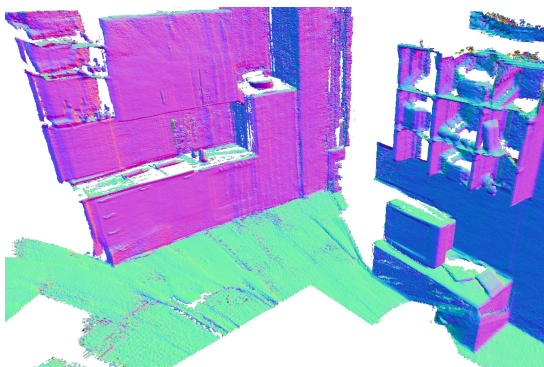
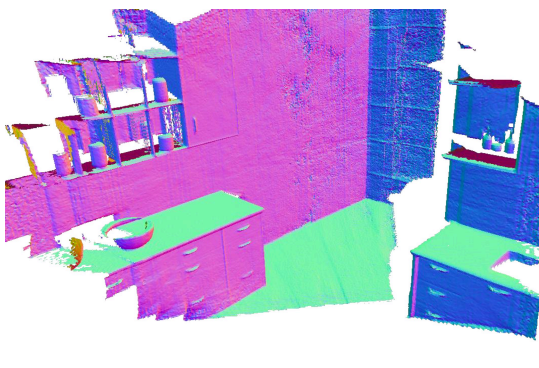


SD

CT

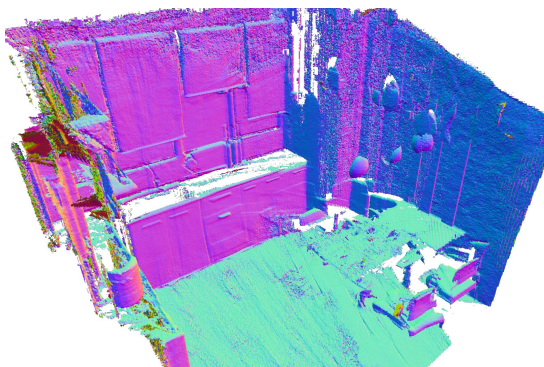


Ours

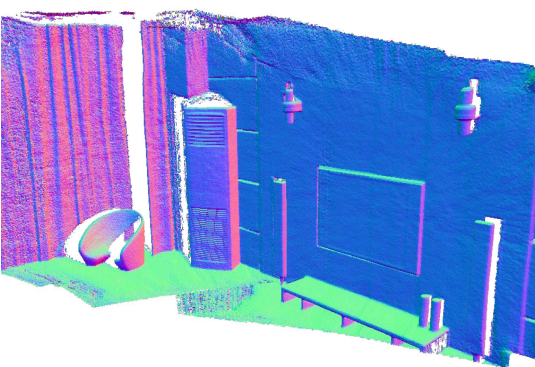
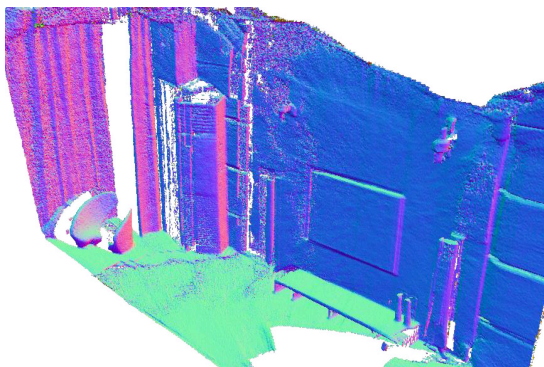
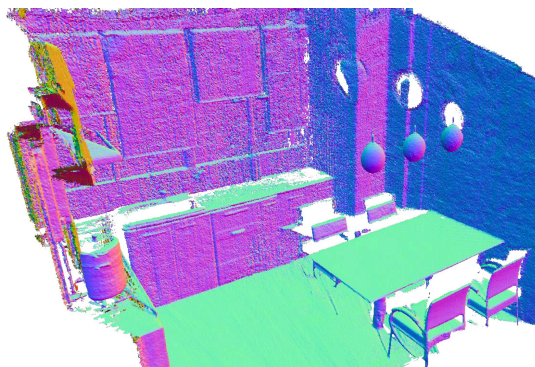


SE

CT



Ours

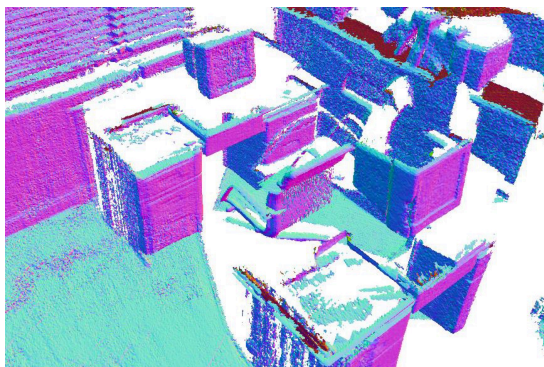
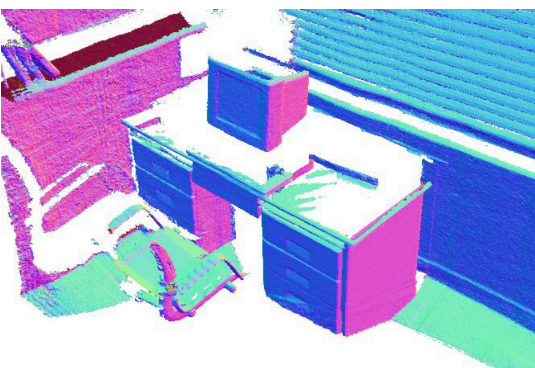


SF

CT

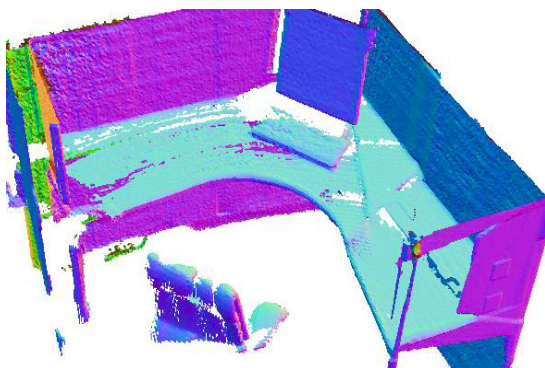


Ours



SG

CT



Ours

