



Figure 5. Face clustering methods: topologydriven methods (on the left) generate a cluster for each face, while octree quantisation correctly gives two clusters (clusters are shown in different colours - see colour plate).

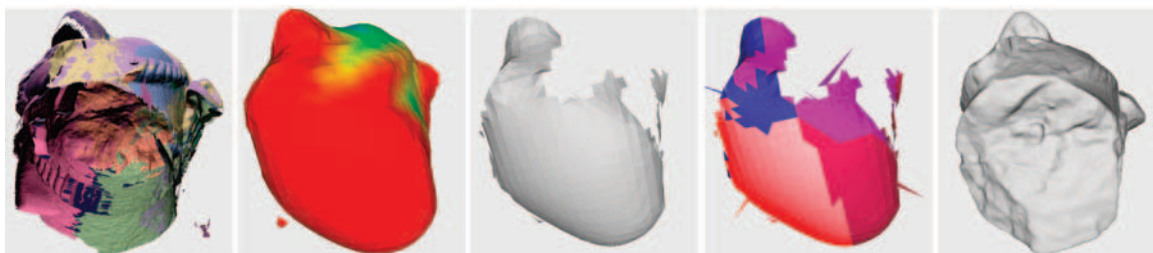
b) Hole maps: different colours refer to different representative normals (i.e. viewpoints). A spike is shown for each viewpoint computed (see colour plate).



(a) Range maps before fusion and the resulting holefree mesh. The colour on the reconstructed surface maps the confidence value using the usual color ramp: red indicates surface portions that were acquired with a low confidence, are sampled in an insufficient way, or are associated to holes.

(b) Hole map and directions resulting from clustering hole map face normals. Each colour encodes a cluster. Spikes represent the viewing poses computed by our algorithm, and are coloured of the same colour of the cluster they represent.

(c) The final model obtained after the corresponding range maps have been acquired and merged into the model.



(d) Some snapshots showing the same model viewed from the bottom. A large hole has been detected and split into a number of distinct clusters. The computed views are shown as spikes. The final model is also shown.

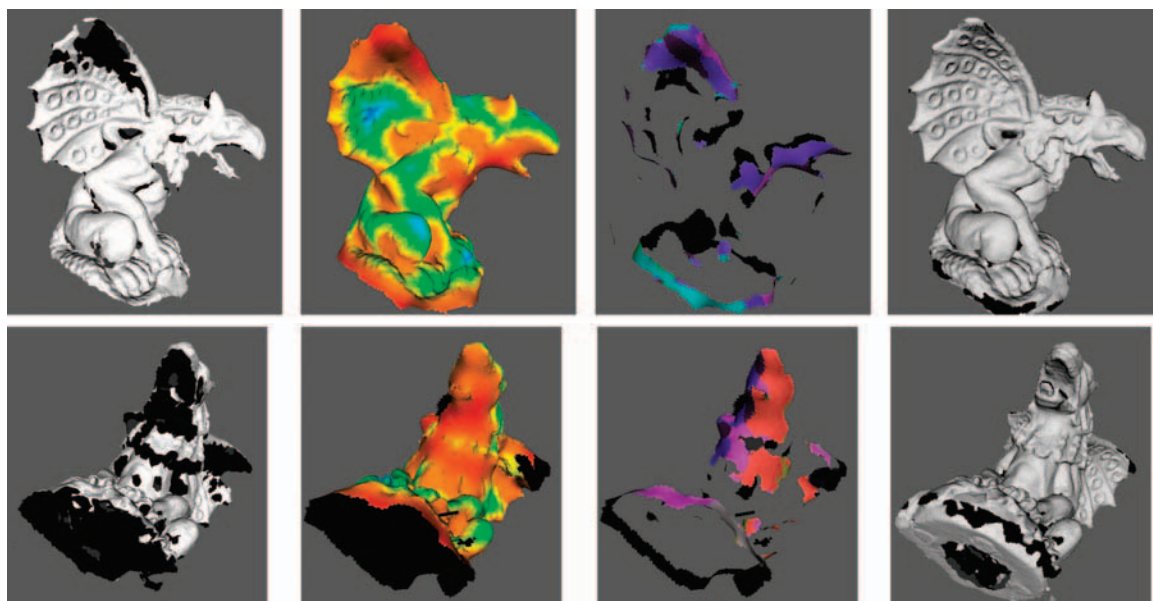


Figure 8. Gap closing of the Gargoyle model (see colour plate). One more iteration of the proposed algorithm is needed to cover the remaining holes.