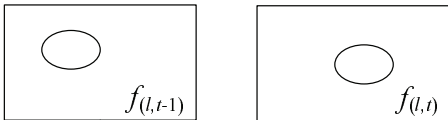


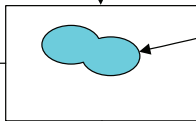
Left view:



Temporal
Change Detection

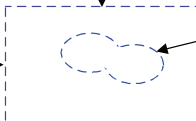
identified change
detection map from
the left view

$$M_{(l, t-1 \rightarrow t)}$$



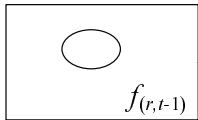
predicted frame
difference for the
right view

$$\Delta f_{(r, t-1 \rightarrow t)}$$



Disparity
Estimation

Right view:



time $t-1$



time t