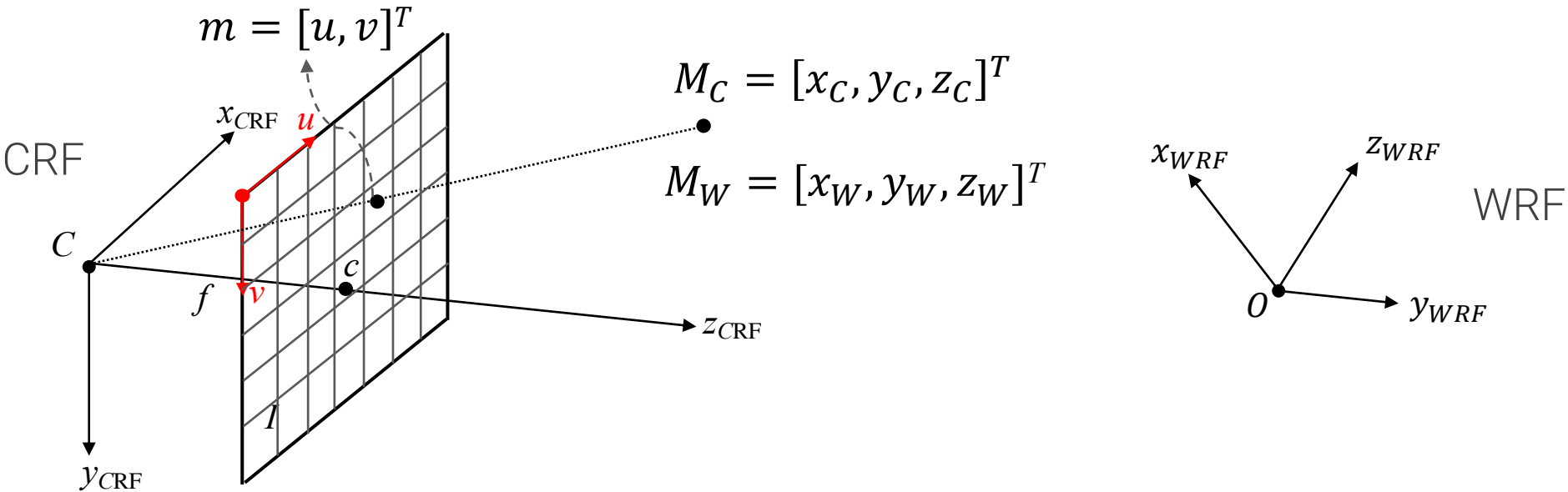
$m = [u, v]^T$
$M_C = [x_C, y_C, z_C]^T$
$M_W = [x_W, y_W, z_W]^T$
CRF
x_{CRF}
u
C
c
f
v
z_{CRF}
I
y_{CRF}
x_{WRF}
z_{WRF}
WRF
O
y_{WRF}