



Fig. 6. Two examples of refinement of a coarse hand model initialization using NBP. We show results following 1, 2, and 4 iterations of the message schedule in Fig. 5. Plots show the projections of the most significant marginal modes.



Fig. 7. Four frames showing extrema of a hand's rigid motion, and the position estimates produced by the NBP tracker.

dynamical models. In addition, we hope to use local hand feature detectors to improve our method's robustness.

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