Real-time Video Mosaic Manual

You can use these arguments in order to achieve better result considering the scene situation.

--source <file address/device number>

Feed the code from a webcam or video file

Example: --source c:\\movie.mp4

Example: --source 0

--x <double>

This will manually set the x coordinate starting point of first image.

Default is in the middle of field of view.

Example --x 1.5

--y <double>

This will manually set the y coordinate of starting point of first image. Default is in the middle of field of view.

Example --y 2

--xscale <double>

This will manually set the field of view in X axis. Default is 4

Example --xsacle 5

--yscale <double>

This will manually set the field of view in y axis. Default is 4

Example --ysacle 5

Motion Estimation Flags:

--detector (fast|surf|orb|fast_grid|orb_grid|surf_grid|sift_grid) <number of features>

You can manually select your detector type. Fast, surf, orb, fast_grid, orb_grid, surf_grid and sift_grid are available.

Default detector is fast and default feature numbers is 300

Example : --detector fast 400

--descriptor (brisk|orb|brief|freak|surf)

Type of features descriptor used for images matching. The default is BRISK.

--match_filter (0|1|2)

Type of filtering good matches. The default is 0. Number 2 means without filter.

--save <file_name>

Save final image to <file_name> file. The default is panorama.jpg

Example: --save panorama_Jahani.jpg

Compositing Flags:

--warp (affine|perspective)

Warp surface type. The default is 'affine'.

--log

Saving the last FOV image automatically when an error occurs. Default is off.

Control Keys:

*****YOU CAN PRESS R TO RESET THE FOV.

*****YOU CAN PRESS E TO EXIT.

The FOV will be automatically saved before RESET and EXIT.