

Visualization of laser scanner point clouds as 3D panorama

Using laser scanning to reconstruct the facade of the Pellerhaus Nürnberg in its historic state

**Adam Kalisz
2265000**

A thesis presented for the degree of
Bachelor in Media Engineering



**TECHNISCHE HOCHSCHULE NÜRNBERG
GEORG SIMON OHM**

Elektrotechnik Feinwerkmechanik Informationstechnik
Georg-Simon-Ohm Technische Hochschule Nürnberg

Thesis advisors:
Prof. Dr. Stefan Röttger
Prof. Dr. (USA) Ralph Lano

Germany
July 2015

Declaration

Plagiarism Declaration in Accordance with Examination Rules

I herewith declare that I worked on this thesis independently. Furthermore, it was not submitted to any other examining committee. All sources and aids used in this thesis, including literal and analogous citations, have been identified.

Signature

Abstract

This study examines a novel approach to convert point clouds generated via laser scanning into textured 3D-meshes. The title of this paper is "Visualization of laser scanner point clouds as 3D panorama". The approach is field-tested with a use case scenario where the interested reader will learn about our research on the 3D-model reconstruction of the historic Pellerhaus in Nuremberg, Germany, as it looked before its destruction during World War II.

Initially, the motivational force, details about the project and existing solutions for creating virtual reconstructions are introduced in Chapter One. The background research that provided necessary fundamentals to start the project, for example how the Pellerhaus evolved or what exactly a 3D panorama is, is described in the second chapter. The third chapter presents the development process of the software tools applied to achieve the goal of reconstructing historic 3D models from various data such as images and laser scans. To accomplish this, a custom converter software has been written, which reads point cloud files and outputs the meshed and textured 3D-object file. The working title of this software is "PointCloud2Blender", *PC2B* in short. As a real world use case the creation of a photorealistic three-dimensional mesh from laser scans via LIDAR devices is described in detail in Chapter Four. Chapter Five concludes the work and presents future work. It contains the results, failures and successes of this research. Furthermore it discusses different possible ways to build upon the fundamental insights gained from this report.

Due to our modern open culture with several open software, hardware and movie projects - mainly inspired by the Blender Foundation - this research is being made available to the public. During the time of the writing of this thesis the progress is therefore published online at <http://bachelor.kalisz.co>.

Acknowledgements

This research could not have been performed without the assistance, patience, and support of many individuals.

On behalf of the historical expertise required for this research, I would like to thank the Geschichtsarchiv Langwasser, including Mrs Edith Schroth and Mr Alfred Schroth for their constant support in providing old photographs, material and making contact to various institutions like archives, museums and companies. They initiated the contact with the Altstadtfreunde Nürnberg e.V. as well. Therefore I would like to thank the Altstadtfreunde Nürnberg e.V. for a huge amount of historic pictures and professional guidance regarding the history of the Pellerhaus. I am happy to get the opportunity to be supported by chairman Mr. Karl-Heinz Enderle during my research.

Secondly, I have to thank my thesis advisor, Mr. Prof. Dr. Stefan Röttger for mentoring me during my undergraduate studies. Not only did he prove his confidence in me by encouraging me to teach computer graphics to other students by letting me demonstrate how much fun it can be creating graphics with the open source 3D graphics suite Blender and offered me several jobs in 3d animation. His insight lead to the initial proposal to examine the possibility of reconstructing the Pellerhaus facade. In addition I would like to extend my gratitude to Mr. Prof. Dr. (USA) Ralph Lano for supervision during my studies. His teaching style and enthusiasm made a strong impression on me and I have always carried positive memories of the classes I attended. Although, the classes I took have not been mandatory and rather seldom they made a lot of fun (e.g. XBox programming with Unity), he was always very helpful and friendly. I would like to thank you very much for your support and understanding over these past four years.

Finally I would like to extend my deepest gratitude to my family without whose love, support and understanding I could never have completed this bachelor's degree.

Contents

1	Introduction	11
1.1	Motivation	11
1.2	Initial project specification	12
1.3	Project schedule	13
1.4	State-of-the-art methods for 3D reconstruction	14
1.4.1	Light Detection And Ranging (LiDAR)	14
1.4.2	Ultrasonic	15
1.4.3	Photogrammetry	15
1.4.4	Depth Cameras	16
1.4.5	Google Maps ®	17
1.4.6	Open Street Map ®	17
1.4.7	Bavarian State Office for Survey and Geoinformation	17
1.4.8	Autonomous mapping with UAV's and SLAM	17
1.4.9	Manual methods	17
1.5	Defining the scope of this research	18
2	Background Research	21
2.1	Historical fundamentals	21
2.1.1	Renaissance	21
2.1.2	Pellerhaus	24
2.1.3	Architects of the Pellerhaus Nürnberg	27
2.2	3D Panorama	27
2.2.1	Creating panoramas	29
2.2.2	Types of projections	30
3	Conversion: From point cloud to Blender 3D	31
3.1	Concept	31
3.1.1	Use case diagram	33
3.1.2	Laser scanning on location	33
3.2	Generating data and testing algorithms	34
3.2.1	BlenSor	34
3.2.2	Test-Addon for Blender	34
3.3	Prototype	35
3.3.1	Point Cloud Importer	35
3.3.2	Determine original point cloud resolution	35
3.3.3	Coordinate system representations	35
3.3.4	Converting from cartesian to spherical and vice versa	36
3.3.5	Types of projections	37

3.3.6	Saving textures	37
3.3.7	OpenGL Point Cloud Viewer	37
3.3.8	Meshing	37
3.3.9	Texture Coordinates and Normals	37
3.3.10	Mesh Exporter	38
3.3.11	Optimizations	38
4	Production: Recreating the Pellerhaus from 1605	41
4.1	Modeling the current Pellerhaus facade	41
4.1.1	Using the PC2B converter software	41
4.1.2	Using UAV references with photogrammetry	41
4.2	Modeling the historic Pellerhaus facade	42
4.2.1	Using historic images as guide	42
4.2.2	Using historic stereoscopic images with photogrammetry	43
4.3	The finished models	43
4.4	Animating between the states	44
4.5	Lighting and Rendering	44
4.6	Stereoscopic Rendering as anaglyph 3d	44
5	Conclusion and Future Work	45
5.1	Conclusion	45
5.1.1	Mesh generation	45
5.1.2	Handling non-LiDAR-Data	45
5.2	Future Work	46
5.2.1	Realtime Conversion	46
5.2.2	Integration in the Blender core	46
5.2.3	3D Lenticular	46
5.2.4	Augmented Reality	46
A	Appendix	47
A.1	Pellerhaus Architect Biography	47
A.1.1	German	47
A.1.2	English	47
A.2	Software used	48
A.2.1	L ^A T _E X	48
A.2.2	Faro SCENE LT	48
A.2.3	Blender 3D	48
A.2.4	Meshlab	48
A.2.5	Visual SfM	48
A.2.6	CMP-MVS	49
A.2.7	Agisoft Photoscan Professional	49
A.3	Programming frameworks and libraries	49
A.3.1	Qt 5.4	49
A.3.2	OpenGL	49

List of Figures

1.1	LiDAR Scanner Point Cloud of the Pellerhaus	14
1.2	Multi-view reconstruction point clouds generated from 356 photos . .	19
2.1	Pellerhaus around 1905	24
2.2	Pellerhaus 2015	25
2.3	The Evolution of the Pellerhaus	25
2.4	2D Panorama of the Pellerhaus	28
2.5	Mapping a two-dimensional panorama onto a three-dimensional sphere	28
2.6	Converting from cartesian to spherical coordinates, visually	29
2.7	Three sample projection types used in PC2B	30
3.1	Use Case Diagram	33
3.2	Scanning with Faro Focus 3D	34
4.1	A description	43
4.2	The Pellerhaus modeled manually	43
4.3	The Pellerhaus modeled manually	44

List of Tables

3.1 Sample generated point cloud files	36
--	----

Chapter 1

Introduction

In this chapter we introduce the project by providing a broad overview of the reason why this topic has been chosen, consideration of various state-of-the-art technologies available for executing the research and the definition what result we expect to get from this report.

1.1 Motivation

The field of 3D computer graphics has always been a fascinating subject to me. Creating virtual worlds and being able to inspect those from every possible viewpoint is a great way to present almost any object one can think of to a wider audience. I finished my apprenticeship as a A/V media designer, so computer graphics are a helpful tool to e.g. previsualize camera work. The best fact about 3D is that it has so many versatile applications in many fields. 3D information can be retrieved from 2D images, taken with a real photo camera, via photogrammetry and can, in turn, be rendered onto a flat computer screen by rendering a three-dimensional scene with a virtual camera. At the point a object is available as a 3D model, it can be postprocessed in various ways. It can be animated, physically simulated and eventually rendered as a video. With modern display technologies the movie can be played out as a stereoscopic one and viewed with anaglyph (red, cyan), polarized, shutter or even without glasses by using e.g. a parallax barrier display (Wikipedia, [Wik14]). Furthermore objects can become tangible via 3D printing or can be inspected interactively in games with the help of virtual reality glasses like the Oculus Rift (Oculus VR, [Ocu15]). It is amazing that anyone can create and enjoy those virtual worlds today.

Additionally, I am highly interested in historical topics. As an active member of a local citizens association and representative of a settlement, where I am always available for any citizenship matters that people might have, I get to know many interesting people and the projects they are working on. Thus I am learning a lot about interesting historical facts and development of culture. Of course, not only about positive history. Especially the history of the place where I live, Langwasser, district of Nuremberg, Germany, is very terrifying and shocking. The district has been formerly used for tent cities and the Märzfeld ("March Field", a representation and parade ground) during the Reich Party Congress in Nuremberg, Germany, between 1933 and 1938 (Wikipedia, [Wik15a]). The construction of a railway station, called Bahnhof Märzfeld which is located right in the center of Langwasser,

was partly finished in 1938. That station has been used initially to transport the members of the Reich Party Congress to the event. During World War II it was used for the deportation of about 940 people to concentration camps, where only 17 of them survived (Stadtteilforum Langwasser, [Sta15]). This railway station is in a ruinous condition at the moment. People go by without noticing that this is real history that passes them by. This was a big concern for me, so I started to search for ways to present history in a modern way, making it educational on the one hand and enjoyable on the other hand.

Consequently, there was the day I talked to my professor, Mr. Dr. Stefan Röttger, about my wish to use laser scanning for historic 3D reconstruction. Surprisingly my professor told me, that we have a laser scanning device at university which could be used for a thesis. The moment he told me that, was the moment I made my decision to center my thesis around laser scanning.

Lastly, a strong motivational force was discovered after researching how the laser scanner point cloud can be used to create the historic building model based off of a recent laser scan. 3D software enables a user to tweak automatically generated meshes or even to add new geometry. Due to my personal experience with the open source 3D graphics suite Blender and the decreasing interest in other software like Autodesk 3ds Max or Maya in favor of Blender (Google Trends, [Goo15]) I decided to use Blender for the 3D modeling and animation part of this research. According to the trend it is a better option since it is being used by a greater number of artists and therefore future work will be of help to a lot of people. In addition, the source code of Blender is open. Any research based on it might benefit other researchers. Thus, it was necessary to be able to work with laser scanner output, namely point clouds, in Blender. Unfortunately Blender is not designed to work with point clouds at the time of this writing. This research should address this issue by providing a way to complete the laser scanning production pipeline for artists who want to use Blender.

As will be described in greater detail hereafter, the aforementioned facts lead to an initial project specification.

1.2 Initial project specification

The idea for this research started with the personal concern of reconstructing a historical site like the old railway station in Langwasser in its historic state. Due to the fact that this railway station has never been fully finished and therefore poor historical documentation, a 3D reconstruction wouldn't be complete. Luckily the famous Pellerhaus was the perfect candidate for this research¹. After its destruction during World War II, it was rebuilt quite differently to the original state. While the inner courtyard is almost finished with reconstruction at the time of this writing, the facade is still looking modern. At that point, it was clear that the main research topic is going to examine ways to reconstruct the Pellerhaus facade in its historic state. A more concrete specification was defined by considering how this is going to be done. The current state of the building has to be captured with laser scanning technology to get the correct measurements from the real world reference. We use a FARO Laser Scanner Focus^{3D} X Series device for this project. This point cloud

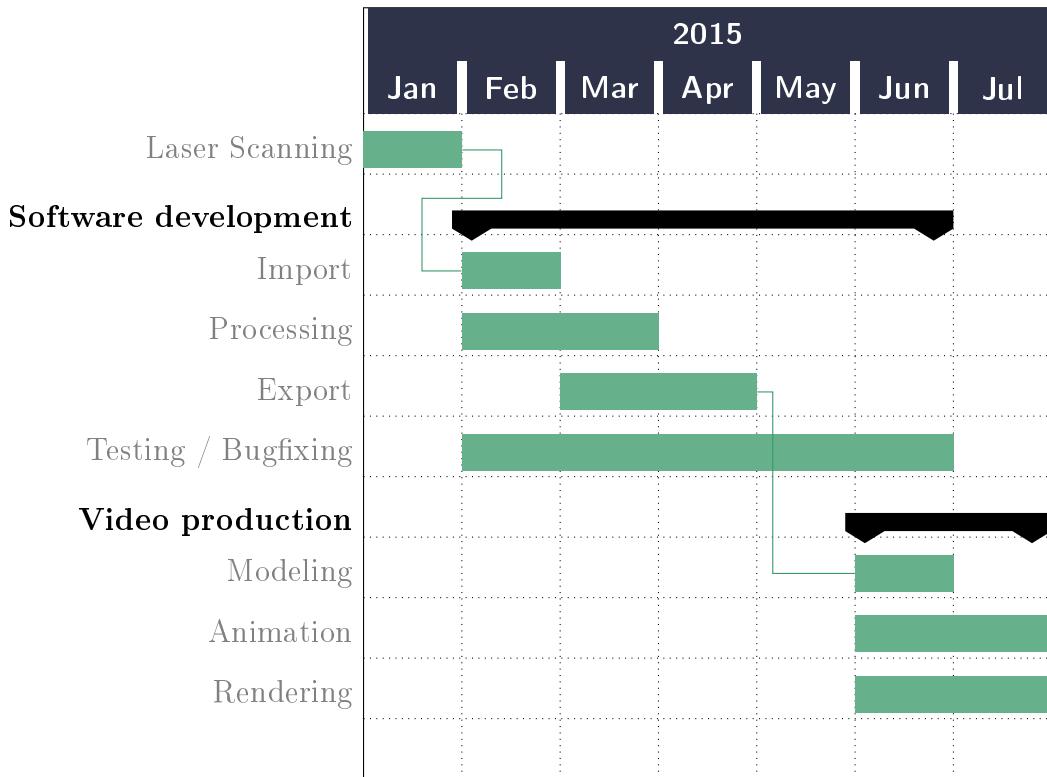
¹Amount of historical photos: Bahnhof Märzfeld: 9; Pellerhaus Nürnberg: 190

data needs to be processed then. To do so, a custom software is required to be written, which can read a file format exported from the proprietary FARO SCENE application, create a panoramic image representation of the data, use it to generate a 3D mesh surface and export this mesh to a widely supported file format. This research will mostly rely on the open source software Blender to model and animate the historic state of the Pellerhaus, thus it is crucial to provide a compatible output to be used as a basis for the design process. By creating a textured surface from the point samples, this research will provide a way for the artist to overcome a bad design decision in Blender, which is making it not capable of displaying or rendering colored point clouds at all (see thread by author on BlenderArtists [Ble14a]). The goal of this research is to get a 3D model of the Pellerhaus in its historic state from 1605 by utilizing point clouds generated via laser scanning as described before.

1.3 Project schedule

This project is divided into two main phases. The first phase is developing the software for converting laser scanner point clouds as 3D panorama meshes. The second one is designing the historic 3D model from this initial mesh.

This is visualized in the following GANTT chart:



1.4 State-of-the-art methods for 3D reconstruction

There are several methods that allow for the generation of 3D meshes from various data. One can either use several still images or videos, sample the real world

with modern sensor technology or use open data for generating geometry of varying complexity. This is described as follows:

1.4.1 Light Detection And Ranging (LiDAR)

The term Light Detection And Ranging (in short LiDAR) is commonly used with high precision applications, such as scanning and mapping of indoor and outdoor environments. It uses a laser beam emitter and receiver. By using the Distance-Speed-Time formula it is very easy to compute how far away an object is:

$$speed = \frac{distance}{time} \Leftrightarrow distance = time * speed$$

The time between sending a signal and receiving it is measured and multiplied by the speed of light ($c = 299,792,458 \frac{m}{s}$, Wikipedia [Wik15b]). This returns the meters the light traveled from the emitter to the obstacle and back. Dividing this distance by two yields the range to the obstacle in meters (Schroeder [see Sch14, p8-9]).

As this gives the meters to only one specific point, it is necessary to keep measuring from different view orientations. This can be done by rotating the scanning device horizontally and vertically simultaneously. To avoid mechanical imprecision or cables from winding up most devices usually use one motor for the horizontal and another motor to control a flat mirror on an elliptical mount for the vertical rotation. That way it is possible to sample a lot of points around the device position quickly and effectively.

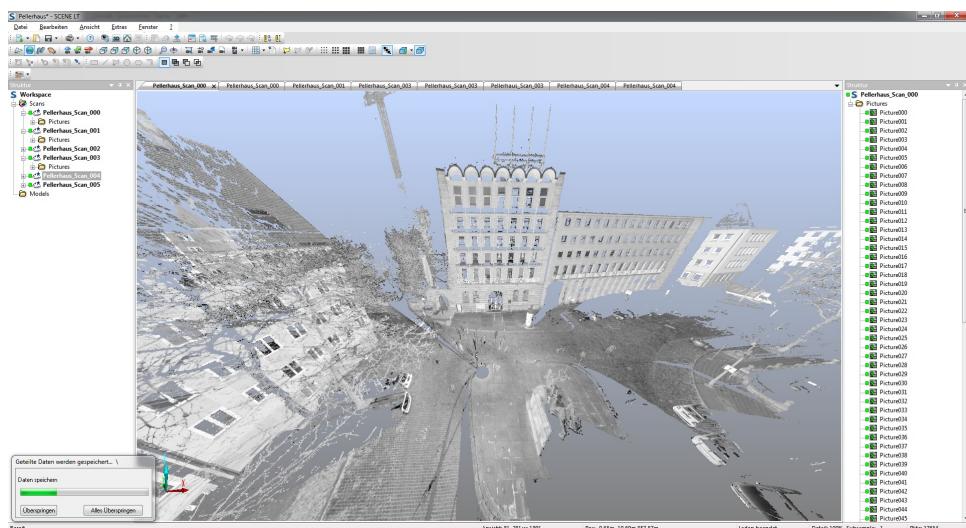


Figure 1.1: LiDAR Scanner Point Cloud of the Pellerhaus

In this work the LiDAR scanner FARO Focus^{3D} is being used. It is capable of capturing 976,000 points per second with a vertical and horizontal field of view of 305 and 360 degrees, respectively (Techsheet FARO Focus^{3D}, [FAR13]). For allowing a better registration additional sensors can be used such as GPS for localization and a barometer for height measurement. The measured points can be colored using an automatic color overlay from a built-in camera at a 70 megapixel resolution. The

price for the Focus^{3D} totals at 61,404.37 Euro (Opti-cal Survey Equipment Ltd. [Opt15]).

Besides using a stationary device, portable devices are also available. Recently a new technology has been revealed by Csiro and is called *Zebedee*. This handheld laser scanner can be used in challenging environments where a stationary device would require several scans to cover the whole area (e.g. caves, staircases) while the operator is walking. It samples over 40,000 range measurements every second and consists of a 2D laser scanner mounted on a spring system (Mail Online, [Vic14]). Especially the visual effects field has a great use for this device, since the environments can vary a lot during video shootings and a 3D mesh representation is ubiquitous today. The price for the ZEB1 handheld laser scanner is 17,000 Euro².

Although measuring with laser technology can be found in household devices as an alternative for tape measuring, it is still quite complicated to reverse engineer such devices to get the raw distance reading. Fortunately a group of engineers tried to bridge the gap by starting a crowd funding campaign for a low-cost laser range finder, called the LiDAR-Lite (PulsedLight [Pul15]). It has a total range of 40 meters with a resolution of 1 cm. During this research this sensor is being used with a custom arduino build to examine how it can be used as a cheap alternative to the examples mentioned in the beginning. The price for one module is at 82 Euro.

1.4.2 Ultrasonic

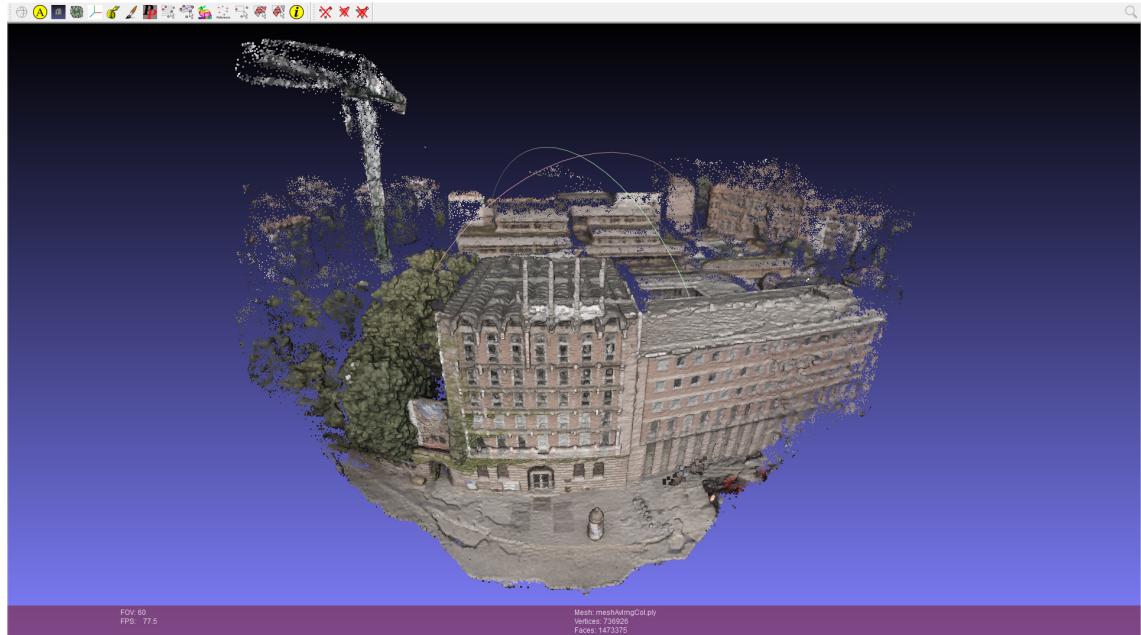
In contrast to LiDAR, most ultrasonic sensors are cheap, but generally are not used for higher distances at several tens of meters (though, there are products for a range higher than 100 meters, compare VEGAPULS 69 [VEG15]). The reason for this is that sound is usually affected stronger by environmental properties than light (compare Sensors Magazine [Sen15]). Due to this they are often used for shorter distances e.g. for near field obstacle recognition in robotics or in small desktop laser scanners (compare Dinh [Huy13]). Typical ultrasonic sensor modules with a maximum range of around 5 m can be purchased for 5 Euro already.

1.4.3 Photogrammetry

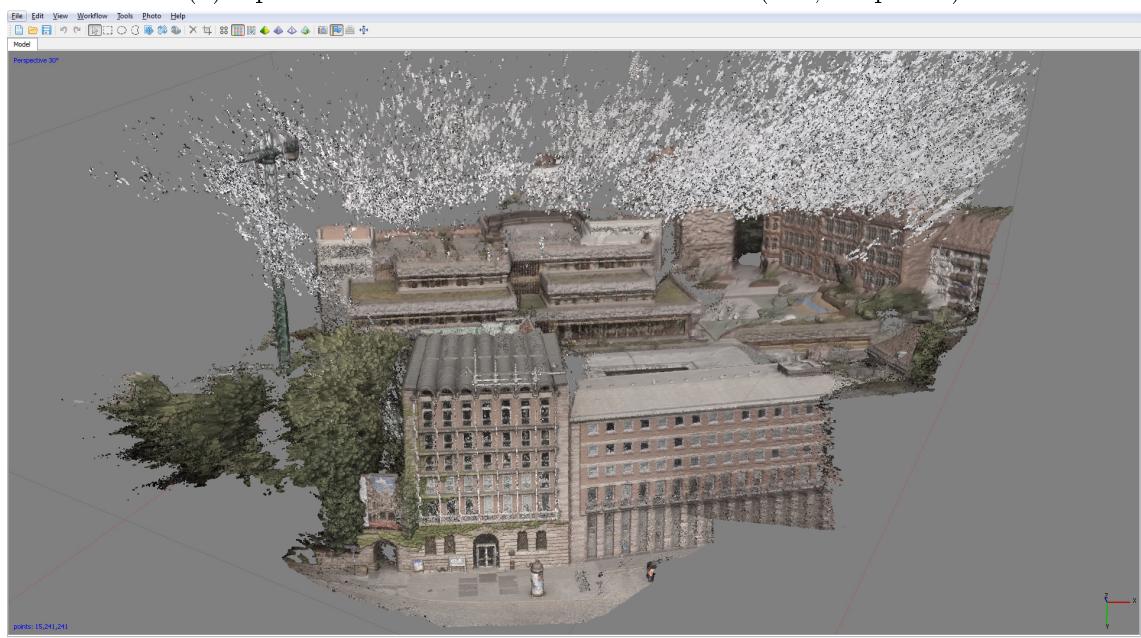
Photogrammetry (also referred to as multi-view reconstruction) is a technique from the Computer Vision field and presents a cost-effective alternative to laser scanning. A real 3D object can be reconstructed as a virtual 3D model by using photographs of the scene and feeding them into such software. This works by detecting image features (for example by using Harris Corner Detector or SIFT algorithms), matching those between image pairs, computing the respective camera positions and re-projecting the reconstructed 3D points to get a point cloud representation of the real photograph (compare Solem [Sol12, p29]). The Computer Vision algorithms get better each day and there is plenty of software using them. Basically we can distinguish between open source, free or commercial software for this task. Usually open source software can be free to use, too. Though, it might have some limitations defined by its license, e.g. only granting non-commercial use. On the contrary, some licenses even allow users to sell the software under a different brand name as is the case with e.g. Blender. In this example the GNU GPL Version 3 license allows a

²Source: Personal contact to sales team

company to sell Blender with prices starting at 47 Dollar. As this is only a side note, more information on that topic can be found in [Ble15]. To compare the results of open source and commercial photogrammetry software we processed 356 photos of the Pellerhaus with two applications. On the one hand VisualSfM for generating a sparse point cloud in conjunction with CMP-MVS for the dense point cloud generation via open source tools have been used. On the other hand the commercial software Agisoft Photoscan Professional was used which costs 3,499 Dollars but can be tested with a fully functional 30 day trial, like in this research.



(a) Open Source: Visual SfM + CMP-MVS (736,926 points)



(b) Commercial: Agisoft Photoscan (15,241,241 points)

Figure 1.2: Multi-view reconstruction point clouds generated from 356 photos

Comparing the results, the point cloud output from Agisoft Photoscan is much

more detailed, approximately by a factor of 20. Furthermore VisualSfM created a bent facade, whereas Photoscan preserved all important straight lines. All in all it can be observed that the algorithms of Photoscan are more sophisticated and suited better for images taken with a great amount of lens distortion, though this is something that should be avoided when considering using the footage for multi-view reconstruction (see Balletti et al. [Bal+14]). Both applications generate a model that can provide a good initial mesh of a scene, but the computation takes very long. Photoscan was using all resources of an eight core Intel i7 workstation with 16 GB of RAM running for about 4 days.

Photogrammetry will be used in this project to try reconstructing surfaces from historical images. Fortunately historical stereographic image pairs are provided through the Altstadtfreunde Nürnberg e.V. By matching the laser scanner data with the Photogrammetry output a good groundwork is expected to be done for the final surface reconstruction.

1.4.4 Depth Cameras

Instead of using photogrammetry software to retrieve 3D information from images, Depth Cameras can be used which encompass the same functionality in hardware. Popular devices are e.g. the Microsoft Kinect v1 and v2 or the Asus Xtion Pro Live, typically ranging between 100 and 200 Euro. Using stereo matching algorithms those devices can determine the distance, or depth, of a certain point. First, an infrared projector emits a speckle pattern which an infrared camera analyzes to match points between the emitter and projector. By using a mathematical process based on trigonometry called Triangulation (compare Wikipedia [Wik15c]) it is possible to calculate the distance to a point if certain properties are known, such as the distance of a fixed baseline between two observing points and the angle from the baseline to the observed point. There are some problems known with those sensors which limit their use mostly to indoor applications. Direct sunlight can wash out the speckle pattern or multiple sensors can confuse each other. Despite those issues Depth Cameras provide a simple and fast way to get 3D point clouds of real objects. Custom software can be written and access this data directly from the depth sensor. The Microsoft Kinect SDK provides some examples how this can be accomplished and the Kinect Fusion project presents a complete solution for creating 3D surfaces of high resolution in real-time (see Newcombe et al. [New+11]).

1.4.5 Google Maps ®

The commercial application allows viewing cities from the sky with a rough representation of 3D building shapes (compare Zamora [Ric14]). While this service had gray boxes some years ago, today the visualization is getting more accurate. Nowadays it is possible to see small details with better modeled and textured buildings.

1.4.6 Open Street Map ®

The open source alternative to the commercial service above offers the basic functions for map viewing and navigation. OpenStreetMap (OSM) offers very detailed access to its data, like boundaries, streets and building footprints. That way it is

possible to extract simple building shapes (compare F4 [F414]) that can be used in custom software free of charge.

To allow for a better mapping of buildings there are also proposals on an indoor version of OSM (compare OpenStreetMap Wiki [Ope15]). Having this data available is a helpful asset for various applications such as indoor navigation at railway and subway stations, mobile emergency exit information and robotics.

1.4.7 Bavarian State Office for Survey and Geoinformation

Geodata and city plans are usually provided officially through governmental institutions. They provide various types of data, among others historical aerial photographs, digital elevation models (DEM) and also 3D building shapes. For educational purposes (like i.e. this research) they offer a university discount for the data of 25 percent. A usual dataset without any discounts containing 7580 buildings of Langwasser, district of Nuremberg in Germany, costs 1,158 Euro³.

1.4.8 Autonomous mapping with UAV's and SLAM

Drones, or unmanned aerial vehicles (UAV's), are getting more popular each day. Most of them are also equipped with a camera which allows for taking pictures or videos from viewpoints a human cannot reach easily. More expensive drones have LiDAR systems attached (Shen et. al. [She10]) which allow - together with the IMU (Inertial Measuring Unit) and GPS (Global Positioning System) to localize it and map its environment. A popular term for retrieving the current position based on various sensor data while creating a virtual representation of the environment at the same time is Simultaneous Localization And Mapping (SLAM).

1.4.9 Manual methods

If all other methods fail, there is still the chance to get a reconstruction done roughly by taking measurements of real objects with measuring tapes or eyeballing. Loading reference pictures from the front, side and top view into a 3D software can already yield decent results. Furthermore this is the standard way a 3D artist would begin to model a digital human or character that a concept artist provided by sketching those three main views of it. Concept art that is accurate and matches every other view can help a 3D artist to block out the shapes very fast. In certain circumstances it can even be faster than setting up a scanning environment or generate a mesh via photogrammetry, because the generated meshes need to retopologized (that is, re-modelled with a strong focus on the clean layout of the mesh grid) anyway as soon as they are considered to be e.g. used in animation.

1.5 Defining the scope of this research

Although this work uses a combination of several techniques (briefly presented above), the main focus is put on examination if panoramic projection and meshing of laser scanner point clouds will be an aid for 3D reconstruction or not. This

³Personal research and contact

will be evaluated by using the result from the custom converter software in a real world use case of using the generated mesh in the design process.

Chapter 2

Background Research

Before we can discuss how the Pellerhaus will be reconstructed by the projection of point clouds as 3D panoramas, it is necessary to build up some fundamental knowledge about the history of the Pellerhaus, define what a 3D panorama is and what properties it has. Those fundamentals will enable us to start with the creation of software tools or 3D models that build upon this basic information. Firstly, we establish a brief historic review of the art epoch in which the Pellerhaus was built to understand the underlying principles of the way it was designed and what it needed to communicate by its authentic style. Secondly, this report presents a definition of the wording "3D panorama" and explains how such a panorama is created from a high-level perspective which prepares the reader for the low-level details in the next chapter.

2.1 Historical fundamentals

2.1.1 Renaissance

We can group certain historical time periods by naming them. For example the time period between the years from 400 to 1499 (often referred to as the 5th and 15th century, respectively) are called the Middle Ages. The time period after the year 1500 (or in other words after the 16th century) is known as the Modern History. We want to take a closer look in-between those two time spans, namely the period from the 14th to the 17th century. This is where the Renaissance art epoch has been active and the Pellerhaus Nürnberg was built. Renaissance literally means "Rebirth" when translated from French. In the Late Medieval period the Renaissance started as a cultural movement in Italy first and spread across the rest of Europe later. Because it is located between the aforementioned time epochs it is considered as the bridge between them. The start of the Renaissance in Italy happened with the support for artistic movements from powerful and dominant families like the Medici, comparable to todays art patronage of digital artists by larger companies (compare Voss 2014 [Geo14] in The Guardian). The Medici family in Florence pioneered the banking system and therefore introduced a commercial revolution to finance the Renaissance.

The Fall of the Constantinople in 1453 at the hands of the Ottoman Turks caused Greek scholars to migrate towards the west. When they arrived in Italy they spread their wisdom and knowledge of ancient Greece and Rome through all the major

city states across the Italian peninsula, such as Florence, Venice, Milan and Rome, during the Renaissance papacy. Thus, the influence of the Renaissance affected the questioning of many aspects in life, like literature, philosophy, art, music, politics, science or religion. Scholars have established new methods in study and introduced realism and human emotion in art.

The principles expressed by the Renaissance are a cultural revival of the ones developed in the ancient Greece and Roman Empire, where for instance in architecture the most representative building was said to be a temple (compare Wikipedia [Wik15d], Architecture section). Since the principles have not been applied uniformly all over Europe the widespread educational reform was gradual. Though, it had a major impact in all aspects of life. In politics it was the base of the conventions of diplomacy and in science the renaissance brought an increased reliance on observing nature instead of pure superstition. The greatest impact, however, was on arts, with discoveries made by famous artists like Leonardo da Vinci and Michelangelo. To summarize, Renaissance could be considered as an attempt to study and improve the physical world by reviving ancient ideas and principles on the one hand and new approaches to thoughts on the other hand.

This revival based on ancient Greek and Roman culture is observed in Renaissance Architecture as well. It followed Gothic architecture and was succeeded by Baroque architecture. The typical Renaissance style in architecture is described by Wikipedia [Wik15e] as follows:

Renaissance style places emphasis on symmetry, proportion, geometry and the regularity of parts as they are demonstrated in the architecture of classical antiquity and in particular ancient Roman architecture, of which many examples remained. Orderly arrangements of columns, pilasters and lintels, as well as the use of semicircular arches, hemispherical domes, niches and aedicules replaced the more complex proportional systems and irregular profiles of medieval buildings.

Renaissance Architecture in Germany

The arrival of the Renaissance architecture in Germany was inspired by German philosophers and artists such as Albrecht Dürer and Johannes Reuchlin. They travelled to Italy, where they learned more about its advanced artistic world. Although the religious turmoil caused by the Protestant Reformation was frequently depicted in arts or literature, gothic and medieval scholastic philosophy remained dominant until the end of the 15th century. When Emperor Maximilian I of Habsburg (1493-1519) rose to power, the Renaissance became popular in Germany, too. Maximilian I was the first true Renaissance monarch of the Holy Roman Empire.

There are several examples of early renaissance architecture in Germany, such as the Landshut Residence or the Augsburg Town Hall, both located in the Free State of Bavaria in the south of Germany. Furthermore the largest Renaissance church was built in Bavaria, too. Sir William V, Duke of Bavaria had to pull down 87 houses, ignoring the protests of the citizens, to construct the St. Michael's Church in Munich between 1583 and 1597.

Along the river Weser in central Germany a specific regional variant of architectural style called the "Weser Renaissance" have been preserved in unusual high

density in towns and cities of that region today. The reason for that is that the economy of the region only recovered slowly from the effects of the Thirty Years War (1618 - 1648) which made them unable to transform to baroque style (compare Wikipedia [Wik15f]).

Nuremberg had substantial achievements in the field of architecture around 1600, too. Some of the most popular projects are described by Mährle (2000) in his book "Academia Norica" [Mäh00] which is translated by the author from German as follows:

Significant public and private buildings have been built between the end of the Second Margrave War and the beginning of the Thirty Years' War.

The first big construction project after the end of the war against Albrecht Alcibiades was the fortification of the defense structures. During 1556-1564, the wall ring was improved and the towers of the five main gates (Laufer Tor, Spittlertor, Frauentor, Neutor, Vestnertor) were surrounded by a stone wall. This was inspired by the towers of Castle Sforza in Milan, Italy.

Additional important public buildings were realized by the city builder Jacob Wolff der Ältere (1596-1612) and his son Jacob Wolff der Jüngere (1612-1620) during that time. The most important ones have been the construction of the Fleischbrücke inspired by the Ponte Rialto in Venice (after 1596), the Wöhrder Torbastei (1613/1614), the master builders' house on the Peunt (1615) and especially the city hall, which was inspired by late renaissance style palaces in Italy (1616-1622).

Besides the public buildings there were several considerable private structures created around 1600. They mostly haven't been commissioned by patricians but rich merchants. The most important ones have been the Toplerhaus (1590), the Fembohaus (1591) and the Pellerhaus (1602-1607).

At the same time many manors in the land domain of Nuremberg have been rebuilt in the following decades after the Second Margrave War.

2.1.2 Pellerhaus

The Pellerhaus was built between 1602 and 1605 and considered one of the most magnificant examples of a town house from German Renaissance architecture.

The house was commissioned to be constructed by the wealthy trading company Viatis-Peller. They have been in the posession of the greatest assets at that time. Bartholomäus Viatis gave the Pellerhaus to his son-in-law Martin Peller where it remained in the posession of the Peller family until 1828.

The house changed owners several times during the subsequent 100 years until it was purchased by the major of Nuremberg in 1929. By acquring the house a proper maintenance of this historic landmark has been assured by the city. It was estimated that a full reconstruction would need the budget of a Martin Peller to succeed. Nuremberg felt responsible for maintaining the beauty of the Pellerhaus at that time and financed a restoration of critical parts of the building. Hence, it started a refurbishment program between 1931

and 1934 for the Pellerhaus, where the focus was put on restoring the delightfulness of the court yard and the rear facade. The red facades have been cleared up and new stone details have been redone by hand. They were really careful to keep all of the small details and not to recreate the house according to a recent art period. The Pellerhaus was saved. Luckily it was at that time, when a vast documentation of the historic Pellerhaus was created. The former restoration is incredible worthy today. Hundreds of plans and photos document every detail of its facade. Without that documentation a reconstruction would have been extremely difficult today (compare Pellerhaus Magazin 2013 [Alt13]).

Unfortunately, Nuremberg suffered from an ally aerial bombing on January 2nd, 1945, as a result of World War II. It was the most severe attack made by aerial bombardment at that time. Nearly 1,800 people have been killed that day. This Area Bombing Directive was issued by the British Air Ministry and directed the Royal Air Force to concentrate their attacks on factorys and industry buildings in general. The objective of the directive was to focus the attacks on the enemy morale. Hence, the bombardment is often called „Morale Bombing“. Many buildings have been transformed into a leveled surface after the removal of the debris remaining from the attack. The bombed areas might either present completely new buildings today or reconstructed ones. The Pellerhaus is a building that has been reconstructed after World War II.



Credit: Altstadtfreunde Nürnberg e.V.

Figure 2.1: Pellerhaus around 1905



Figure 2.2: Pellerhaus 2015

Figure 2.2 shows the Pellerhaus in 2015. The building is a large, multi-story brick structure with arched windows and a prominent statue of a man on a horse in front. A banner hangs from the left side of the building. The reconstruction was initiated in 1955. It only preserved the base floor in its historic state, due to the fact that some major parts of it have survived the bombing. From the first floor upwards, the facade of the Pellerhaus changed dramatically and only served a pure functional purpose, as room was needed to accommodate the new City Library and Archive. It was almost decided to completely embed the Pellerhaus into the Library which has been built to the right of it. But there was a certain force within the city that did not allow that. An old arc has been completely destroyed to connect the Pellerhaus with the Library, which is criticized as being senseless. Only some column bases and capitals were still laying in the inner courtyard and were ready to be build into the southern part of the court. So, all six arcs, the little passage next to the front-facing house and the adjacent facade part of the northern court facade needed to be recreated. So, in the end, the old style Pellerhaus was combined with a new style to allow experiencing the old state at least a little. The reconstruction of the base floor was finished in 1957. The upper floors - and therefore all reconstruction efforts - have been finished by 1960. At that time people realized that a full reconstruction might happen some day, although the individual storey heights differ from the original. Conversely, when a secondary school was built on top of the back-facing house in 1972/73, almost any hope of a full reconstruction of the Pellerhaus was killed (compare Pellerhaus Magazin 2012 [Alt12]).

The reconstruction was initiated in 1955. It only preserved the base floor in its historic state, due to the fact that some major parts of it have survived the bombing. From the first floor upwards, the facade of the Pellerhaus changed dramatically and only served a pure functional purpose, as room was needed to accommodate the new City Library and Archive. It was almost decided to completely embed the Pellerhaus into the Library which has been built to the right of it. But there was a certain force within the city that did not allow that. An old arc has been completely destroyed to connect the Peller-



Credit: Carl Simon United Archives

(a) before 1945



Credit: Life Archive

(b) Pellerhaus 1945



(c) after 1945

Figure 2.3: The Evolution of the Pellerhaus

In 2005 a new initiative was launched, which had the goal of reconstructing the Pellerhof, which is the inner courtyard of the Pellerhaus. With its groined vaults, it is an artistic piece of architecture. The association Altstadtfreunde e.V. created

a flyer [Alt] which includes a wonderful description of the Pellerhaus that has been translated by the author from German:

Before destruction, the Pellerhaus was one of the main sights of Nuremberg. The architecture seems to be the most honorable performance of the local art of construction. Its inner court was considered the probably most beautiful arcade court.

As the city descended into shatters in 1945, there were only a few remains of the Pellerhaus. The front-facing house was rebuilt in a modern form 1957 on top of the reconstructed hall. An enourmous effort was done by complementing the courtyard, it was discontinued 1959, though.

Not until 2005, 60 years after the destruction, the Altstadtfreunde took the initiative to continue the former abandoned construction of side wing and rear house facade.

With the accurate documentation of the pre-war level it is possible to do those court additions with extraordinary accuracy. October 2008 layed the foundation block of building the courtyard completely via donations. Since then with the well corner, side wings and eastern backyard gallery crucial parts have been able to get restored from the old building.

With your donation or by purchasing a symbolic block of stone you can help to make one of the greatest achievements of German Renaissance come alive in its historic state.

At the time when the merchant Martin Peller started with building his house in 1602, he also layed the foundation block to what later entered as the most magnificant bourgeois house into the history of art. The notion of building an arcade court was not new in Nuremberg. There have been hundreds of gallery courts in the city. Many of them with tracery breastwork made of stone. Though, the Pellerish courtyard bested everything that has been known at that time:

On the two long sides it was flanked by noble three-story arcades, with a clear and symmetric structure, though with a rich and filigreed ornamentation. While skimming along it, ultimately the show façade caught the eye with a glorious gable. Seldom one can find forms of the italian renaissance merged with local sensuous enjoyment in such a happy way. Antique style pillars accompany the individual floors, obelisks stretch up into the sky and still the appearance was entirely different than in Italy. The Pellerhof, as a Middle European counterpart to the wonderful arcade courts of Italy, is an indispensable part of european architecture

.

This project is still active today and the Pellerhof has almost been fully reconstructed by the Altstadtfreunde Nürnberg e.V. at the time of this writing. The build process was mainly based on photos and the remains of the western side. Measurements have been extracted by examining the remains like profiles, design of capitals and ending stones. Overall forms were reconstruced with the help of historic photos. New constructions were needed for the differing tracery of balustrade areas. It was a stroke of luck that the historic documentation of the house is extensive. This helped even with differences of geometrically correct constructions with the new

build. Also the Chörleins are documented well enough to allow for a reconstruction. For example, there is a massively wrong ornamentation of Chörleins at window lintels, sockets, and volutes when comparing the rebuild from 1950 with the original. On the contrary, we are much closer at the renaissance original with our new build. The Altstadtfreunde Nürnberg e.V. can proudly say that with their restored state the two time layers 1605/07 and 1957/59 form a harmonic unit. From April 2013 they moved newly produced stone blocks and a fully donated arc in the Pellerhaus. Once again, they noticed the reckless deviation of any regularity. All of the six arcs have different spans and the alignment of the arcarde row is not straight, but has been – in its old parts – slightly bulged out. Though, this might be due to the bombing destruction, just as the fact that the arc row doesn't continue horizontally but considerably descends from the front-facing house into the courtyard.

The facades of the buildings in Nuremberg have been painted red with white rectangles some times. The reason for this was that the look of mined stones varied quite a lot. So by painting them the houses had a united look. This color is also called the „Nürnberger Rot“ (Terra Norimbergensis rubra), because it is looking like the local sand stone and the color powder is coming from the rural area of Nuremberg. Unfortunately only a few color remains are left but it is enough to prove the colorfulness of the facade. After finishing the reconstruction in the courtyard repainting the facades in the „Nürnberger Rot“ would be the right decision (compare Pellerhaus Magazin 2014 [Alt14]).

With the ongoing progress of the reconstruction of the Pellerhof, our research will examine ways to reconstruct the historic Pellerhaus facade as a 3D model.

2.1.3 Architects of the Pellerhaus Nürnberg

The Pellerhaus was constructed by the German architect Jakob Wolff der Ältere who was born in Bamberg in 1546. He accomplished some famous building projects in Nuremberg, such as the Fleischbrücke. He had two sons, Hans and Jakob Wolff der Jüngere. They have been educated by their father and built the city hall of Nuremberg.

A detailed biography about the architects can be found in the Appendix (A.1).

2.2 3D Panorama

The term "panorama" is defined by Wikipedia [Wik15g] as follows:

A panorama (formed from Greek $\pi\hat{\alpha}\nu$ "all" + $\hat{o}\rho\alpha\mu\alpha$ "sight"), is any wide-angle view or representation of a physical space, whether in painting, drawing, photography, film, seismic images or a three-dimensional model. The word was originally coined in the 18th century[1] by the Irish painter Robert Barker to describe his panoramic paintings of Edinburgh and London. The motion-picture term panning is derived from panorama.

In simple words this means that we can create a two-dimensional image containing every view one can see from a fixed position. This is an example how this can look for the Pellerhaus:



Figure 2.4: 2D Panorama of the Pellerhaus

The image above was generated with the custom PointCloud2Blender (PC2B) converter software which will be discussed in detail in the next chapter. A two-dimensional panorama image depicts a full horizontal and vertical view of the location where it was taken from. Please note, that the example above is not a full vertical view. The reason being, this image was generated from a point cloud of a laser scanner. Due to the tripod on which the scanner was mounted on, the lower part of the scan is useless and therefore has been omitted by the scanning device.

This two-dimensional panorama can now be converted to a three-dimensional panorama by simply mapping it onto a sphere, as shown here:



(a) 2D Panorama mapped on a unit sphere



(b) The same panorama mapped on a sphere using individual distances

Figure 2.5: Mapping a two-dimensional panorama onto a three-dimensional sphere

Placing a virtual camera in the center of the sphere, makes it possible to visualize the complete three dimensional environment from one viewpoint.

3D Panoramas got a great new use by the introduction of the Oculus Rift (Oculus VR, [Ocu15]). Nowadays they are increasingly used in film production as well. While this technique was used rather seldom in e.g. the Circle-Vision theaters in Walt

Disney Theme Parks in 1955 (see Wikipedia [Wik15h]), todays hardware is getting cheaper and faster to create such panoramas in real-time. The German FMX 2015, one of the biggest international Conferences on Animation, Effects, Games and Transmedia, presented several software and hardware solutions that were able to stitch multiple video feeds into one panorama (compare Kolor [Kol15]). A very sophisticated example of using video panoramas combined with Visual Effects is Google ATAP ‘HELP’ (compare CGMeetup, [CGM15]) which is a video that can be viewed interactively on mobile devices from every angle by simply pointing the device in the desired direction.

2.2.1 Creating panoramas

To create panoramic images it is necessary to map a three-dimensional environment onto a two-dimensional plane. This is accomplished by computing the spherical coordinates of every point in three-dimensional space. Without going into too much technical detail, we can either define a point in 3D space with its x, y and z coordinate (known as the cartesian coordinates) or with their horizontal angle displacement, vertical angle displacement and distance from the origin (which is known as spherical coordinates). The latter can be imagined as rotating and scaling a unit sphere until it intersects the point.

To clarify the process a little further, we will do a visual example. Consider the 3D point A at $(1.0, 1.0, 1.41421)$ in cartesian coordinates (x, y, z) . We need to align the x-axis of a unit sphere, labeled Point B, with point A (Figure 2.6a). To do so, we first rotate the sphere along its local z-axis by 45 degrees (Figure 2.6b). Secondly, we rotate it along its local y-axis by 45 degrees (Figure 2.6c). Finally we scale the unit sphere by 2 to align both points with each other (Figure 2.6d). Now we have calculated the spherical coordinates (θ, φ, r) which are now expressed as $(45.0, 45.0, 2.0)$. This process is visualized below:

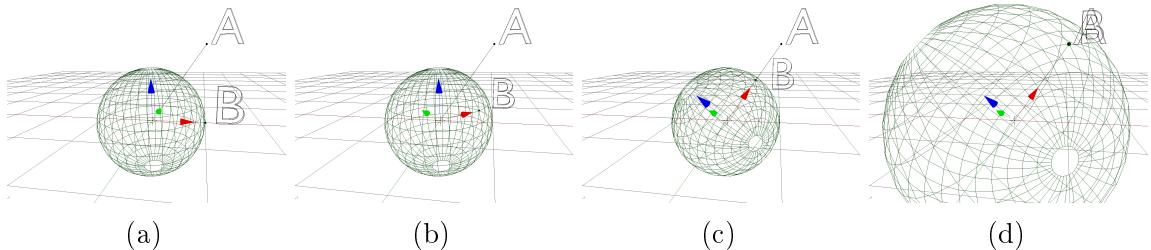


Figure 2.6: Converting from cartesian to spherical coordinates, visually

The final image can be formed by mapping these spherical coordinates (θ, φ, r) to the image coordinates (x, y) . This is called panoramic projection.

There is a set of various types of projections used for panorama generation. A subset of them is introduced in the following section.

2.2.2 Types of projections

It is not possible to create a perfectly "flat" or two-dimensional representation of a sphere. There will always be distorted areas, thus it is necessary to choose the right projection type for every new task (compare Furuti [Car14]).

A study of implementing seven different projections was conducted by Houshia et al. [Hou+15] in 2015. The findings of that study are the basis for our implementation in the converter software. We have implemented three projections, namely the equirectangular, cylindrical and mercator projections.

The equirectangular projection is the simplest type and can be implemented very fast, as the spherical coordinates θ and φ are mapped directly to the x and y coordinates of the two-dimensional image without any transformation.

Next, the cylindrical projection is similar, but the vertical mapping is transformed. This can be envisioned by placing a sphere inside a cylinder. If light is emitted from the center of the sphere it is projected onto the cylinder. The projection keeps vertical lines straight, horizontal lines are still curved, though. Furthermore objects are stretched vertically, which gets more prominent the closer they are to the north and south poles of the sphere.

Lastly, the mercator projection is a mapping that preserves angles locally (conformal projection). The distortions are less pronounced than equirectangular or cylindrical projections.

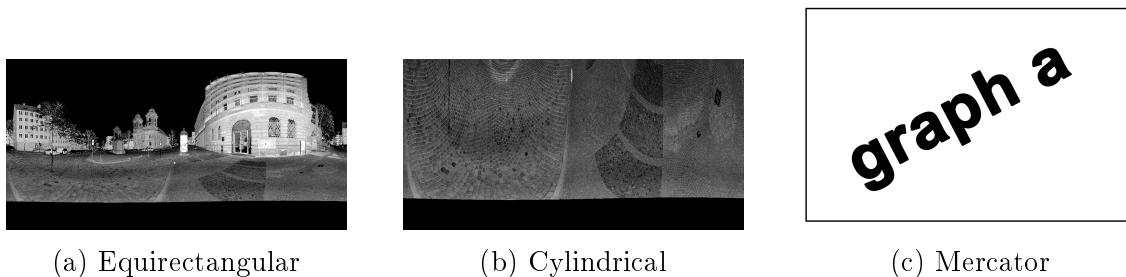


Figure 2.7: Three sample projection types used in PC2B

One of the most spread types is the equirectangular projection (see Figure 2.7a). Furthermore it does not apply any transformation or scaling. During testing it proved as the only useful projection, since the other projections caused a lot of points to stretch into negative infinity. Due to this reason we use it primarily in this project.

Chapter 3

Conversion: From point cloud to Blender 3D

This chapter presents the implementation of a custom software tool, which creates panoramic images based on point clouds captured e.g. via laser scanning. We discuss every step in the development phase from concept to finished prototype. It is developed with the version control system git and hosted in a public repository on GitHub.com. The software development progress is recorded via screen capturing and will gradually be uploaded online. Additionally, this information is provided on the official website which accompanies our research.

3.1 Concept

Based on the initial idea to somehow move from a dense point cloud to a 3D mesh surface that can be used in the 3D graphic suite Blender, it was important to plan ahead.

It is possible to mesh a 3d point cloud with several algorithms by trying to find the nearest neighbour of a point in 3d space. One such algorithm is called Delaunay Tetrahedralization (see: <http://www.cs.berkeley.edu/jrs/papers/cdtbasic.pdf>) and is used in the free multi-view reconstruction software "Visual SfM", for instance.

With our method we try to utilize the characteristics of laser scanners in such a way, that we know every acquired point can be described by scaling and rotating a unit sphere. In mathematical terms we can determine the spherical coordinates of every point in our point cloud. The 3d points need to be converted from their cartesian coordinate system to the spherical coordinate system first (see http://en.wikipedia.org/wiki/Coordinate_system). Using this simple principle we can not only mesh a point cloud generated by a laser scanner, we can texture it, too. With the coordinates ranging from 0 to 360 degrees horizontally, 0 to 180 degrees vertically and a depth coordinate ranging from 0 to the maximum scan distance we are able to create two images, namely a depth map and a color map. Those images are then being used to create a regular grid which is used for meshing and texture coordinates. By applying the inverse transform to the spherical coordinates it is possible to get the model in cartesian space and export it to any 3d file format. This process is explained in more detail in this chapter.

Furthermore it was necessary to know how the user will be operating with the software. Usually a use case diagram is created to determine the required functions

the software must provide in order to let a user accomplish his desired goals.

3.1.1 Use case diagram

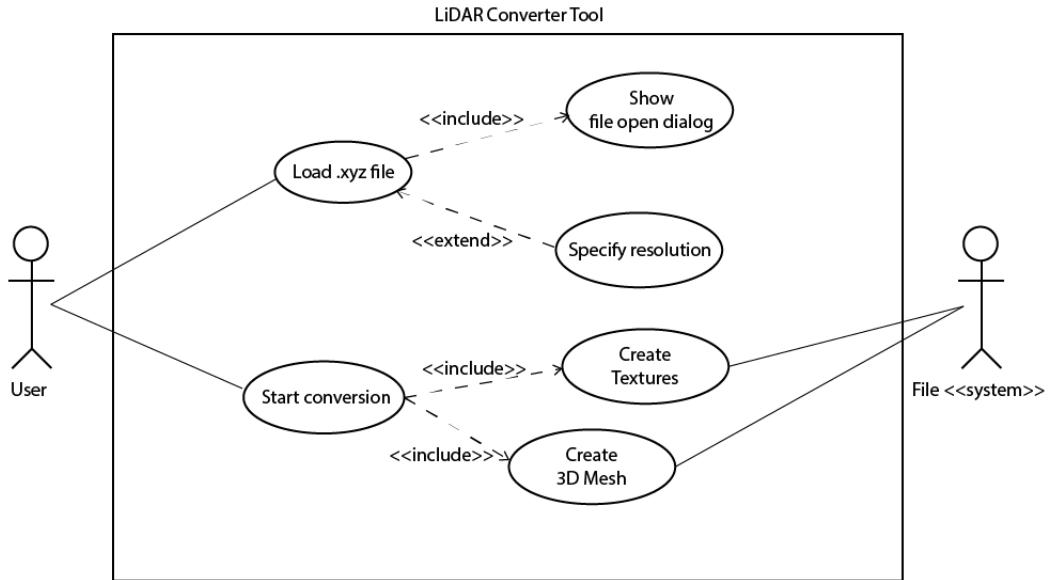


Figure 3.1: Use Case Diagram

3.1.2 Laser scanning on location

For data acquisition we used the Faro Focus 3D laser scanner on the 21.1.2015 16:39:15. First, the device should be configured by setting e.g. the desired resolution (for scan and photos), maximum scan distance (which results in a change of the eye-safety distance), a project name and GPS location (if no GPS module is available like in our case). This configuration can be done in the office or on-site. After the device was set up, the scan process was started. During scanning the main body rotates horizontally and a mirror mounted inside the body rotates vertically. This creates the uncolored point cloud. After the scanning process, several pictures are taken by the built-in camera to color the point cloud. Beforehand the scanner measures the exposure to avoid under- or overexposed photographs. Finally, the inclination is measured with an inclinometer to level the point cloud properly. This procedure was repeated five times to get additional scans covering viewpoints that have been obstructed by obstacles.

While scanning a site we faced problems we didn't expect. We encountered people randomly walking in the laser beam (resulting in vertical lines in the final scan), a surprisingly occurring crash of the device's operating system leading to a terminal output (wrecking the sd card with all previous scans) and a man asking if we took a photo of him while he was entering the building(?!).



Figure 3.2: Scanning with Faro Focus 3D

3.2 Generating data and testing algorithms

3.2.1 BlenSor

The Blender Sensor Simulation Toolbox (compare [Gsc+11]) is a custom version of the open source software Blender allowing to simulate different types of scanning within a virtual 3d scene. It is being developed by the Department of Computer Sciences, University of Salzburg, Austria. The goal of this project is to provide a tool, mostly aimed at researchers, that can help with testing algorithms for fields such as obstacle detection and tracking, range data segmentation or surface reconstruction. We found this software very useful to begin with the development of PC2B. With a number of scanner presets it is possible to generate a point cloud of the virtual environment from different types of scanner devices.

3.2.2 Test-Addon for Blender

During the beginning of the software development process the point cloud projection didn't seem to be correct. Testing the algorithm responsible for projecting from cartesian to spherical coordinates was very tedious, because it involved importing the files, waiting for the images to get generated and then either look at the image files to find mistakes or continue with the meshing process. This pipeline was prone to errors which might affect the result.

Hence, a custom addon for Blender was developed to test the algorithm for the

correct mathematics. The language used for addons is Python 3 and enables for developing powerful extensions to the Blender core.

A more efficient approach would be to develop a new modifier in C/C++ that integrates directly into Blender. Unfortunately diving into Blender Core Development is not very easy due to its huge code base. In addition the time constraint didn't permit experimenting further with this approach.

3.3 Prototype

The working title of the converter software was defined as "PointCloud2Blender", PC2B in short, because this was the main goal of the software project.

3.3.1 Point Cloud Importer

A crucial part of the PC2B converter software is the ability to import point clouds saved as files. There is a huge amount of file types that can accomodate such a data structure. Points can be stored in ASCII or Binary form. Importing binary formats requires to know the exact structure of the file and the bytes used for certain values. Documentation was limited for many of the file formats, so using ASCII files was a better choice from the beginning. Initially it was planned to only import the .xyz file format, since this is a very simple file format that can be exported in ASCII form from the proprietary Faro SCENE 5 software which is needed for preprocessing the raw point cloud stream produced by the Faro Focus 3D.

During development it turned out that support for the .ply file format is desirable, since scientific websites that provide models (see) widely provide this file type. Also Blender can export a 3D model to this file format. This fact was extremly useful for testing the algorithm, which is described later.

Point Cloud data formats

Working with such file structures like in our case is very easy. See 3.1.

3.3.2 Determine original point cloud resolution

Users of PC2B have the option to determine the resolution of the 3D panorama. It can either be set to fixed multiples of 360 by 180 pixels or set to a custom resolution. We have implemented an algorithm to help the user find the best resolution for his particular point cloud. It works as follows:

3.3.3 Coordinate system representations

We can express points in different coordinate systems. For example cartesian, cylindrical and spherical.

Almost all point cloud files use a cartesian coordinate system (at least the ones we are using). To get the coordinate of a point in an image plane from a point in cartesian space, we simply convert its coordinate space from cartesian to spherical. We then have the points horizontal position in a range of 360 degrees and its vertical

```
ply
format ascii 1.0
comment VCGLIB generated
element vertex 2900882
property float x
property float y
property float z
property uchar red
property uchar green
property uchar blue
property uchar alpha
element face 0
property list uchar int vertex_indices
0.480478 -0.877007 0.000000 -0.479092 0.877764 0.000000
0.477702 -0.878522 0.000000 -0.479092 0.877764 0.000000
0.477702 -0.878522 0.661730 -0.479092 0.877764 0.000000
0.480478 -0.877007 0.661730 -0.479092 0.877764 0.000000
-0.373352 0.927690 0.000000 0.371881 -0.928280 0.000000
-0.370417 0.928866 0.000000 0.371881 -0.928280 0.000000
-0.370417 0.928866 0.661730 0.371881 -0.928280 0.000000
-0.373352 0.927690 0.661730 0.371881 -0.928280 0.000000
0.110288 0.993900 0.000000 -0.111863 -0.993724 0.000000
0.113431 0.993546 0.000000 -0.111863 -0.993724 0.000000
0.113431 0.993546 0.661730 -0.111863 -0.993724 0.000000
0.110288 0.993900 0.661730 -0.111863 -0.993724 0.000000
...
...
```

(a) Sample .xyz file

(b) Sample .ply file

Table 3.1: Sample generated point cloud files

position in a range of 180 degrees. In that way we create the image files from the point samples and then use those images to convert back to the cartesian space.

3.3.4 Converting from cartesian to spherical and vice versa

To convert from Cartesian space to spherical coordinates, we use the following equation:

$$\text{radius} = \sqrt{(x^2 + y^2 + z^2)}$$

$$\theta = \text{atan2}(y, x) + \pi$$

$$\phi = \cos^{-1}(z/\text{radius})$$

(see [PH10], page 114)

Conversely, to get from spherical to cartesian coordinates, we use:

$$x = r * \sin \theta * \cos \phi$$

$$y = r * \sin \theta * \sin \phi$$

$$z = r * \cos \theta$$

(see [PH10], page 114)

This is inside the text $\cos(2\theta) = \cos^2 \theta - \sin^2 \theta$.

And this is a separate formula:

$$\cos(2\theta) = \cos^2 \theta - \sin^2 \theta$$

3.3.5 Types of projections

To convert from Cartesian space to spherical coordinates, we have the option to use various projection types, as already briefly introduced in 2.2.2.

Equirectangular projection

$$\theta =$$
$$\theta =$$

Cylindrical projection

$$\theta =$$
$$\theta =$$

Mercator projection

$$\theta =$$
$$\theta =$$

3.3.6 Saving textures

The generated depth and color maps are stored with 8-bit unsigned integer values ranging from 0 to 255. After the file has been imported they can be saved directly as .jpg image files.

3.3.7 OpenGL Point Cloud Viewer

This russian video tutorial was very helpful with the basic setup with the Qt framework.

[Enz14]

3.3.8 Meshing

Using the current pixel inside two for-loops in combination with the neighboring pixels to the right, bottom-right and bottom makes up a quad, which can be textured.

3.3.9 Texture Coordinates and Normals

Texture Coordinates go from 0.0 to 1.0 in the x and y direction, respectively. Usually the texture coordinate axes are referred to as s and t. By dividing the current coordinate by the width and the height of the image, respectively, the coordinates can be normalized.

Calculating normals is accomplished by using the cross product of the two vectors forming the current quad.

3.3.10 Mesh Exporter

There are different formats, one had to be chosen that supported at least vertices and faces.

.obj

The .obj format is the most popular and can be one of the easiest to understand file formats to save 3D geometry with not only points, but vertices, normals, texture coordinates and much more. It was the first choice when testing mesh exporting from the converter software and examining it in Blender.

.blend

A personal goal for this research was to implement a .blend export feature to allow for a native importing of the panorama mesh into Blender. However, this goal was not reached in this project. As it turned out, exporting the binary Blender file format was quite complicated, due to its versatile structure. An experienced Blender Developer, Jeroen Bakker, stated in 2009 “When implementing loading and saving blend-files in a custom tool the difficulty is the opposite. In a custom tool loading a blend-file is easy, and saving a blend-file is difficult.” [Bak09, see]. At least implementing it with the limited time for the thesis it was not feasable.

custom format

Even the Blender community suggested to not use the .blend format directly, but rather try a custom binary format. [Ble14b, compare]

3.3.11 Optimizations

The initial algorithms and approaches had some flaws, which needed to get eliminated to get a clean mesh out of the converter. Those are presented as follows:

Flip horizontal direction of panorama

The panorama is flipped horizontally.

Panorama pixel depth testing

It can happen that two points from the point cloud happen to result in the same pixel in the 2D panorama. This might result in a noisy image result, if not handled with care. To avoid any errors, it is important to take only the closest point to the camera, instead of letting every point override the corresponding pixel in the image.

Panorama noise reduction

Since there is only a limited number of points, the panorama texture gets quite noisy, especially with a higher resolution option set in the converter. A harsh change from light gray to black values in the depth map will result in a noisy 3D structure as well. To solve this issue, the image is blurred by a user setting or automatically (TODO!).

Remove doubles

The meshing technique resulted in a very high point count for the .obj file. Example: For a 4x resolution panorama with 2,198,528 vertices, using the "remove doubles" option in Blender 3D automatically removed 2,100,716 vertices. Solution: several passes for vertices, texture coordinates and normals (TODO!).

3D Distortion

The generated 3D mesh from the 2D panorama results in a distorted one, the more it touches the top. Solution: None yet.

Tiling

Due to the higher resolution meshes having several megabytes in size and taking some time to import in Blender, this has to be optimized somehow. Solution: Create tiles when higher resolution is set. E.g. with a 4x resolution, create four tiles (that's four separate .obj files).

Chapter 4

Production: Recreating the Pellerhaus from 1605

The generated mesh may still need additional cleanup and detail. The topology is dependend on the used meshing algorithm, naturally. The laser scanner beam cannot sample reflective or transparent structures. It can only provide a great reference for manual tracing.

4.1 Modeling the current Pellerhaus facade

The lower part of the Pellerhaus facade is very similar, almost identical, to the historic one. Thus modeling the modern facade based on LiDAR, photogrammetry and photographic reference appeared to make sense.

4.1.1 Using the PC2B converter software

Firstly, the LiDAR data was preprocesed in PC2B. We created five scans on location, so all scans have been preprocessed and imported into Blender.[Sch14].

4.1.2 Using UAV references with photogrammetry

Unmanned Aerial Vehicles (UAV's or simply drones) are getting affordable, even very good quality models. In our research we use the DJI Phantom 2 with a GoPro Hero 4 Black mounted on a 3-axis DJI Zenmuse H3-3D Gimbal to create photographic aerial references of the Pellerhaus Nürnberg.

Flying a drone inside the city center of Nuremberg is not as easy, as it might be assumed at first. Before even being able to take off with a UAV, German law requires a general permission for just entering the air space. In addition every UAV pilot needs an UAV insurance.

Regarding the usage of drones in the city center, there are more restrictions. The city center of Nuremberg is covered by the controlled air space. Flying in that air space is not permitted until the starting permission from the bavarian aviation authority and UAV insurance are upgraded to commercial ones. Furthermore pilots need a clearance from the Air traffic control (ATC). Additionally the starting and landing procedure requires to cordon off pedestrians and a special license from the

traffic authority. Lastly, the owner of the property needs to be asked for permission to allow the starting and landing of the aircraft.

Luckily there are some laws that permit video shoots and taking photos. For example the Freedom of panorama (§ 59, German Urheberrechtsgesetz) allows taking photos from pavements and roads permanently located in a public place. This right to freely take and share photographs of buildings and works of public art may be abolished on July 9th, 2015 by the European Parliament (see [Owe15]). We expect immense implications on historic documentation of buildings if this happens.

In total we made three flights on location. It was planned to use the second flight for single photos shot in an interval of 1 second whereas the other two flights are videos in 4K. Unfortunately, it turned out that the third flight wasn't recorded at all and the second flight was captured as a video file. Luckily we noticed the third video missing while still on location, having a bit of battery life left and about one hour left to use the air space, so we made at least two impressive aerial shots before ending the mission.

With having video files instead of still images, those needed to be exported as still frames to be able to be processed by software. We tried both the free "Visual SfM" and commercial "Agisoft Photoscan Pro" software solutions to generate additional colored meshes of the Pellerhaus. The total processing time of about 20 hours for Visual SfM and 40 hours for Photoscan to get a 3D point cloud from the images. Comparing the results we noticed that Visual SfM generated a bent facade while Photoscan Pro kept it very straight. Although not recommended in (), we used a GoPro camera with a short focal length and thus a strong lens distortion for 3d reconstruction. We can confirm, that the use of this camera is not a good choice, since the radial distortion can produce errors in the feature matching phase of photogrammetry. Still the output should be a good reference for the rough shape of the reconstructed object. If available, LiDAR data should be used for accurate building reconstruction.

4.2 Modeling the historic Pellerhaus facade

Based on the modern facade it was possible to get a good feel for the size of the Pellerhaus in the renaissance. Still the main parts above the ground floor of the facade differ dramatically from the modern one. They can only be extracted from photographs.

4.2.1 Using historic images as guide

It is a huge luck that the Pellerhaus history has been documented by an enormous amount of pictures. A big load of about 190 pictures has been provided for free through the Altstadtfreunde Nürnberg e.V. association, not including about 100 additional pictures depicting the space in front of the building.

Those pictures can be traced in Blender.

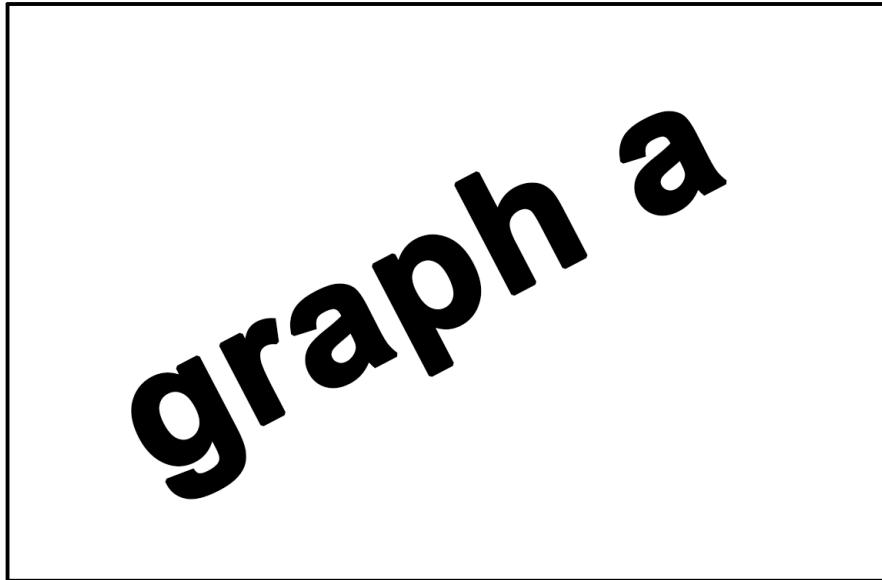


Figure 4.1: A description

4.2.2 Using historic stereoscopic images with photogrammetry

Although the historic pictures have already been a blessing, there are two images acquired by stereophotography. Trying to feed the left and right image into photogrammetry software, respectively, gives a nice 3d representation of the historic facade already. Of course, little details are still missing.

4.3 The finished models



(a) Modern Pellerhaus



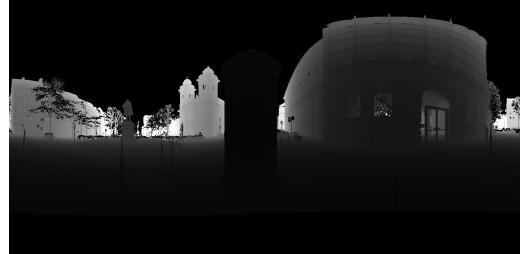
(b) Historic Pellerhaus

Figure 4.2: The Pellerhaus modeled manually

The modeling process is finished with the creation of the destructed Pellerhaus, which basically only consists of the base floor.[compare][webLaTeX-Tutorial].



(a) Colormap



(b) Depthmap

Figure 4.3: The Pellerhaus modeled manually

4.4 Animating between the states

Since the created models are very similar in size, it is possible to animate a simple fade between them. A more interesting solution is a fracturing simulation, though.

4.5 Lighting and Rendering

The models need to be evenly lit.

4.6 Stereoscopic Rendering as anaglyph 3d

For a better presentation, the scene can also be visualized in stereoscopic 3d. Through the newly implemented stereo feature in Blender this is now a hassle-free process.

Chapter 5

Conclusion and Future Work

5.1 Conclusion

To conclude, in this work we presented a method to process a point cloud file with a custom software to get a textured mesh ready to use in Blender (or any other 3d software package) and examined the use of the generated mesh for designers with the use case of reconstrucing the historic Pellerhaus Nürnberg. This approach led to an easy way to get a mesh from a point cloud. The goals have been met and the reaults can be worked with (TODO: correct grammar and spelling ;)).

5.1.1 Mesh generation

Lorem ipsum dolor sit amet, consectetur adipiscing elit. Nullam hendrerit interdum sagittis. Nulla facilisi. Pellentesque laoreet tincidunt semper. Pellentesque pellen-tesque lectus id arcu interdum cursus ut ac dui. Etiam feugiat nisl ac odio suscipit pretium venenatis eget diam. Morbi molestie ipsum sit amet sapien rutrum luctus. Proin ac dolor ut metus laoreet aliquam non id nunc. Curabitur non efficitur dolor. Donec iaculis, dui et porta iaculis, magna tellus placerat ex, sed porta sem ligula ac augue. Fusce vitae sagittis ex. Pellentesque faucibus cursus elit, et faucibus velit cursus in. Nam lobortis id neque id hendrerit. Fusce et dolor nisi.

5.1.2 Handling non-LiDAR-Data

Although the goal for this work was to

Additionally, Mrs. Eichhorn, a fellow student finishing her bachelor's degree in October 2015, teamed up with me to examine ways how this research can be used with a depth sensor. She wrote a custom tool to save the output of a depth sensor to an .xyz file which is compatible with the PC2B converter software. The results are great, showing that it is possible to generate 3D panoramas from depth sensors as well. The test data has XXX points and is processed in YYY milliseconds in the PC2B converter. [...]

-Title: Selbstständige Navigation eines autonomen Roboters mittels 3D-Tiefensensor
-Description: kommt noch -Deadline: 13.August will ich abgeben, aber spätestens geht auch 16.10 -Colored Point Cloud file: ... wird auch nachgereicht ...

5.2 Future Work

There are some further ideas how the software and how the 3D model can be used in other fields of application.

5.2.1 Realtime Conversion

Etiam non volutpat diam. Nam ac consectetur felis. Ut nec mi dictum, lobortis mauris quis, dapibus ligula. Nulla porttitor diam sed mauris dapibus posuere. Fusce pellentesque odio at nisl placerat porta. Donec urna risus, iaculis vitae justo quis, tempus ullamcorper diam. Integer eu gravida est. Phasellus eu ex tincidunt urna tempus pulvinar in in metus. Mauris tempus magna ac finibus suscipit. Praesent malesuada magna nibh, at rutrum felis semper a.

5.2.2 Integration in the Blender core

Aliquam at varius elit. Suspendisse viverra ex a ipsum scelerisque condimentum. Nam ac neque luctus, ullamcorper neque sit amet, tincidunt felis. Maecenas id orci rutrum, tincidunt nisl non, aliquam sapien. Aenean vestibulum erat ut nisl vehicula, quis rutrum eros fermentum. Maecenas ut arcu elit. Cras vestibulum pharetra facilisis. Quisque non elit iaculis leo dignissim faucibus. Etiam fringilla tortor nibh, sit amet volutpat diam consequat ac. Sed consectetur metus quis suscipit sollicitudin. Morbi imperdiet scelerisque nunc, in dapibus lacus. Praesent ullamcorper condimentum augue vitae finibus.

5.2.3 3D Lenticular

Interdum et malesuada fames ac ante ipsum primis in faucibus. Cras quis pharetra libero. Pellentesque consectetur, quam vel ultrices finibus, sem enim consectetur mi, in dictum tellus leo eu ante. Maecenas consequat egestas erat, in vestibulum velit pulvinar ac. Suspendisse ullamcorper augue sapien, ac suscipit nulla dictum in. Nam sit amet congue ipsum. Aenean non felis malesuada, feugiat lectus a, tincidunt quam. Fusce nec quam egestas, vulputate est in, commodo nisi. Phasellus id nunc sit amet quam iaculis ornare eu id libero. Ut tempor nisi sed est pretium auctor. Donec in nunc turpis. Integer non tristique dolor. Curabitur a elit mollis urna finibus scelerisque sit amet vel erat. Nullam nec maximus erat. Duis ante mi, posuere ut lobortis nec, posuere eu ligula.

5.2.4 Augmented Reality

Having a 3D model of the historic Pellerhaus opens a whole new set of possible new ways to communicate the history. Example: "Timetraveler The Berlin Wall App" (<https://www.youtube.com/watch?t=75&v=CY9f6UJZlmM>)

Appendix A

Appendix

A.1 Pellerhaus Architect Biography

A.1.1 German

Körner, Hans-Michael and Jahn, Bruno (2012, p.2128) [KJ12] wrote a detailed biography about the architects of the Pellerhaus Nürnberg:

Wolff, Jakob d.Ä., Baumeister, Bildhauer, * um 1546 Bamberg, † 4.4.1612 Nürnberg

W. wurde 1596 Stadtbaumeister in Nürnberg, wo er mit seinem Sohn Jakob -> W. d.J. die Fleischbrücke errichtete. 1601-05 beteiligte er sich am Neubau der Feste Marienberg in Würzburg und am Umbau des Echertors. Sein Hauptwerk ist das Pellerhaus in Nürnberg (1602-07), einer der vornehmsten Privatbauten der deutschen Renaissance (im Zweiten Weltkrieg zerstört; die Reste des Arkadenhofs wurden in den modernen Bau einbezogen).

LITERATUR: Wilhelm Schwemmer: J.W. der Ältere und der Jüngere. In: Fränkische Lebensbilder. Bd. 3. Hrsg. v. Gerhard Pfeiffer. Würzburg 1969, S. 194-213.

Wolff, Jakob d.J., Baumeister, *1572 Bamberg, † 24.2.1620 Nürnberg

W. war Schüler seines Vaters Jakob -> W. d.Ä., erhielt 1605 in Nürnberg die Stelle eines Stadtwerkmeisters, hielt sich mit Erlaubnis des Rats u.a. in Bayreuth, Frauenaurach und Schwabach auf und begann, beeinflußt von der niederländischen und italienischen Renaissance, 1616 mit dem Neubau des Rathauses in Nürnberg, der 1622 von seinem Bruder Hans vollendet wurde.

A.1.2 English

Körner, Hans-Michael and Jahn, Bruno (2012, p.2128) [KJ12] translated from German by the author:

Wolff, Jakob d.Ä., master builder, sculptor, *1546 Bamberg, † 4.4.1612 Nuremberg

Wolff became the city architect of Nuremberg in 1596, where he and his son W. d.J. built the Fleischbrücke. During 1601-05 he took part in the new build of the stronghold Marienberg in Würzburg and in the reconstruction of the Echtertor. His principal work is the Pellerhaus in Nuremberg (1602-07), one of the most noble private properties during the German Renaissance (destroyed in the Second World War; the remaining parts of the arcade court have been included in the modern building) [...]

Wolff, Jakob d.J., master builder, *1572 Bamberg, † 24.2.1620 Nuremberg

Wolff was the student of his father W. d.Ä., was given the job of a Stadtwerkmeister (Municipal Master of the Works) in 1605, had the permission from the council to stay in Bayreuth, Frauenaurach and Schwabach and started, influenced by the Dutch and Italian Renaissance, with the new build of the city hall in Nuremberg in 1616, which was finished by his brother Hans in 1622.

A.2 Software used

A.2.1 L^AT_EX

This paper was written in L^AT_EX. On Windows, TeXstudio in conjunction with MikTeX (both portable versions) have been used for visual creation of the document. I decided to switch from the free version Adobe InDesign CS 2.0 to L^AT_EXin favor of it being cross-platform and hoping to make it easier to publish the thesis online in the future. Since I have never worked with L^AT_EXbefore, various tutorials [Sha13; Vel15] on the internet have been a great help.

A.2.2 Faro SCENE LT

For preprocessing of the raw laser scanner point cloud. <http://www.faro.com/faro-3d-app-center/stand-alone-apps/scene-lt>

A.2.3 Blender 3D

To cleanup the generated mesh, retopologize it and create the 3D animations of the Pellerhaus, Blender was used. <http://blender.org>

A.2.4 Meshlab

For converting binary test files to ASCII. <http://meshlab.sourceforge.net/>

A.2.5 Visual SfM

For creating 3D models from images for free. <http://ccwu.me/vsfm/>

A.2.6 CMP-MVS

For creating dense reconstruction based on camera parameters. <http://ptak.felk.cvut.cz/sfmservice/websfm.pl?menu=cmpmvs>

A.2.7 Agisoft Photoscan Professional

For creating 3D models from images with a 30-day test period. Mostly historic stereo pairs have been processed well. <http://ccwu.me/vsfm/>

A.3 Programming frameworks and libraries

A.3.1 Qt 5.4

Qt is an open source framework ...

A.3.2 OpenGL

The Open Graphics Library (OpenGL) is an abstraction layer for accessing graphics hardware on a high level. The current version supports the programmable function pipeline, where vertex and fragment shaders provide a rich set of ways to manipulate the final pixel on the output device, e.g. computer screens. ...

Bibliography

- [Wik14] Wikipedia. *Parallax barrier* — Wikipedia, The Free Encyclopedia. 2014. URL: https://en.wikipedia.org/w/index.php?title=Parallax_barrier&oldid=612869363 (Retrieved 06/19/2015).
- [Ocu15] Oculus VR, LLC. *Oculus - Oculus VR*. 2015. URL: <https://www.oculus.com/en-us/> (Retrieved 06/19/2015).
- [Wik15a] Wikipedia. *Nazi party rally grounds* — Wikipedia, The Free Encyclopedia. 2015. URL: https://en.wikipedia.org/w/index.php?title=Nazi_party_rally_grounds&oldid=664601942 (Retrieved 06/19/2015).
- [Sta15] Stadtteilforum Langwasser. *Langwasser! Geschichte eines neuen Stadtteils*. 2015. URL: <http://stadtteilforum.org/langwasser/langwasser-geschichte/tafel-6.html>.
- [Goo15] Google Inc. *Google Search Trends: Blender, 3ds Max and Maya*. 2015. URL: <https://www.google.com/trends/explore#q=/m/011qq,%20/m/01tgyn,%20/m/0svhm&cmpt=q&tz=Etc/GMT-2> (Retrieved 06/19/2015).
- [Ble14a] Adam Kalisz (BlenderEi). *Point Cloud support in Blender: What's already there and what does the community need*. 2014. URL: <http://blenderartists.org/forum/showthread.php?349851-Point-Cloud-support-in-Blender-What-s-already-there-and-what-does-the-community-need> (Retrieved 01/24/2015).
- [Wik15b] Wikipedia. *Speed of light* — Wikipedia, The Free Encyclopedia. 2015. URL: https://en.wikipedia.org/w/index.php?title=Speed_of_light&oldid=667601477 (Retrieved 06/20/2015).
- [Sch14] Rayk Schroeder. “Was kann eigentlich dieser LIDAR-Scanner? (German) [What is this LIDAR-Scanner capable of?]” In: *Digital Production* 07 / 14 (2014), pp. 8–9.
- [FAR13] FARO Technologies Inc. *FARO Focus^{3D} Features, Benefits and Technical Specifications*. 2013. URL: <http://www2.faro.com/site/resources/share/944> (Retrieved 06/20/2015).
- [Opt15] Opti-cal Survey Equipment Ltd. *Opti-cal Survey Equipment - FARO Focus 3D X 330 Laser Scanner*. 2015. URL: <http://surveyequipment.com/faro-focus-3d-x-330-laser-scanner/> (Retrieved 06/22/2015).

- [Vic14] Victoria Woollaston. *The 'Prometheus' scanner that can 3D scan capture a crime scene in minutes*. 2014. URL: <http://www.dailymail.co.uk/sciencetech/article-2562329/Prometheus-style-scanner-maps-crime-scenes-3D-rotated-tagged-without-damaging-evidence.html> (Retrieved 06/20/2015).
- [Pul15] PulsedLight. *PulsedLight / PulsedLight*. 2015. URL: <http://pulsedlight3d.com/> (Retrieved 06/22/2015).
- [VEG15] VEGA Grieshaber KG. *Radarsensor zur kontinuierlichen Füllstandmessung von Schüttgut – VEGAPULS 69*. 2015. URL: http://www.vega.com/de-DE/home_de/Produkte/Produktkatalog/F%C3%83%C2%BCllstand/Radar/VEGAPULS%2069 (Retrieved 06/22/2015).
- [Sen15] Sensors Magazine. *Choosing an Ultrasonic Sensor for Proximity or Distance Measurement Part 1: Acoustic Considerations / Sensors*. 2015. URL: <http://www.sensorsmag.com/sensors/acoustic-ultrasound/choosing-ultrasonic-sensor-proximity-or-distance-measurement-825> (Retrieved 06/22/2015).
- [Huy13] Huy Dinh. *VGU.EXCELSIOR - Ultrasonic 3D Scanner - Vietnam MCU Contest 2013*. 2013. URL: <https://www.youtube.com/watch?v=salWhEYQxTg> (Retrieved 06/22/2015).
- [Sol12] Jan Erik Solem. *Programming Computer Vision with Python*. Sebastopol, CA 95472: O'Reilly, 2012.
- [Ble15] Blender Foundation. *Re-branding Blender - blender.org - Home of the Blender project - Free and Open 3D Creation Software*. 2015. URL: <https://www.blender.org/press/re-branding-blender/> (Retrieved 06/24/2015).
- [Bal+14] Caterina Balletti et al. “Calibration of Action Cameras for Photogrammetric Purposes”. In: *Sensors* 14.9 (2014), p. 17471. ISSN: 1424-8220. DOI: 10.3390/s140917471. URL: <http://www.mdpi.com/1424-8220/14/9/17471>.
- [Wik15c] Wikipedia. *Triangulation — Wikipedia, The Free Encyclopedia*. 2015. URL: <https://en.wikipedia.org/w/index.php?title=Triangulation&oldid=663507003> (Retrieved 06/25/2015).
- [New+11] Richard A. Newcombe et al. “KinectFusion: Real-time Dense Surface Mapping and Tracking”. In: *Proceedings of the 2011 10th IEEE International Symposium on Mixed and Augmented Reality*. ISMAR '11. Washington, DC, USA: IEEE Computer Society, 2011, pp. 127–136. ISBN: 978-1-4577-2183-0. DOI: 10.1109/ISMAR.2011.6092378. URL: <http://dx.doi.org/10.1109/ISMAR.2011.6092378>.
- [Ric14] Ricardo Zamora. *Google Maps 3D*. 2014. URL: <https://www.youtube.com/watch?v=5iolZU8LwPU> (Retrieved 06/22/2015).
- [F414] F4. *F4map Demo - Interactive 3D map*. 2014. URL: <http://demo.f4map.com/#lat=49.4559869&lon=11.0762814&zoom=18> (Retrieved 06/22/2015).

- [Ope15] OpenStreetMap Wiki. *Indoor Mapping – OpenStreetMap Wiki*. 2015. URL: http://wiki.openstreetmap.org/wiki/Indoor_Mapping (Retrieved 06/22/2015).
- [She10] Shen, Shaojie and Michael, Nathan and Kumar, Vijay. *Autonomous Aerial Navigation in Confined Indoor Environments*. 2010. URL: <https://www.youtube.com/watch?v=IMSozUpFFkU> (Retrieved 06/22/2015).
- [Geo14] Georgina Voss. *DevArt: Google's powerful new move to arts patronage / Science / The Guardian*. 2014. URL: <http://www.theguardian.com/science/political-science/2014/feb/28/devart-googles-powerful-new-move-to-arts-patronage> (Retrieved 06/25/2015).
- [Wik15d] Wikipedia. *Greco-Roman world — Wikipedia, The Free Encyclopedia*. 2015. URL: https://en.wikipedia.org/w/index.php?title=Greco-Roman_world&oldid=654515334 (Retrieved 06/25/2015).
- [Wik15e] Wikipedia. *Renaissance architecture — Wikipedia, The Free Encyclopedia*. 2015. URL: https://en.wikipedia.org/w/index.php?title=Renaissance_architecture&oldid=665879352 (Retrieved 06/25/2015).
- [Wik15f] Wikipedia. *German Renaissance — Wikipedia, The Free Encyclopedia*. 2015. URL: https://en.wikipedia.org/w/index.php?title=German_Renaissance&oldid=645400210 (Retrieved 06/26/2015).
- [Mäh00] Wolfgang Mährle. *Academia Norica*. Berlin: Franz Steiner Verlag, 2000, pp. 39–40. URL: <http://www.steiner-verlag.de/titel/51429.html> (Retrieved 03/11/2015).
- [Alt13] Altstadtfreunde e.V. *Pellerhaus Magazin 02. Ein Magazin der Altstadtfreunde zum Wiederaufbau des Pellerhofes*. German. 2013.
- [Alt12] Altstadtfreunde e.V. *Pellerhaus Magazin 01. Ein Magazin der Altstadtfreunde zum Wiederaufbau des Pellerhofes*. German. 2012.
- [Alt] Altstadtfreunde e.V. Wiederaufbau des Pellerhofes. German. In: () .
- [Alt14] Altstadtfreunde e.V. *Pellerhaus Magazin 03. Ein Magazin der Altstadtfreunde zum Wiederaufbau des Pellerhofes*. German. 2014.
- [Wik15g] Wikipedia. *Panorama — Wikipedia, The Free Encyclopedia*. 2015. URL: <https://en.wikipedia.org/w/index.php?title=Panorama&oldid=665030494> (Retrieved 06/27/2015).
- [Wik15h] Wikipedia. *Circle-Vision 360 — Wikipedia, The Free Encyclopedia*. 2015. URL: https://en.wikipedia.org/w/index.php?title=Circle-Vision_360%C3%82%C2%B0&oldid=666618020 (Retrieved 06/27/2015).
- [Kol15] Kolor Team. *Kolor / Image-stitching, virtual tour, 360-degree video experts*. 2015. URL: <http://www.kolor.com/> (Retrieved 06/27/2015).
- [CGM15] CGMeetup. *Google ATAP 'HELP' Behind The Scenes Computer Graphics and Digital Art Community for Artist: Job, Tutorial, Art, Concept Art, Portfolio*. 2015. URL: <http://www.cgmeetup.net/home/google-atap-help-behind-the-scenes/> (Retrieved 06/27/2015).
- [Car14] Carlos Alberto Furuti. *Map Projections: Mapping Definitions and Concepts*. 2014. URL: <http://www.progonos.com/furuti/MapProj/Normal/CartDef/MapDef/mapDef.html> (Retrieved 06/27/2015).

- [Hou+15] HamidReza Houshia et al. “A Study of Projections for Key Point Based Registration of Panoramic Terrestrial 3D Laser Scans”. In: (2015), pp. 11–31. DOI: 10.1080/10095020.2015.1017913.
- [Gsc+11] Michael Gschwandtner et al. “BlenSor: Blender Sensor Simulation Toolbox Advances in Visual Computing”. In: ed. by George Bebis et al. Vol. 6939. Lecture Notes in Computer Science. Berlin, Heidelberg: Springer Berlin / Heidelberg, 2011. Chap. 20, pp. 199–208. ISBN: 978-3-642-24030-0. DOI: 10.1007/978-3-642-24031-7_20. URL: http://dx.doi.org/10.1007/978-3-642-24031-7%5C_20 (Retrieved 05/31/2015).
- [PH10] Matt Pharr and Greg Humphreys. *Physically Based Rendering, Second Edition: From Theory To Implementation*. 2nd. San Francisco, CA, USA: Morgan Kaufmann Publishers Inc., 2010. ISBN: 0123750792, 9780123750792.
- [Enz14] Ivan Enzhaev. *Qt C++ OpenGL GLSL (parts 1 to 8)*. 2014. URL: <https://www.youtube.com/watch?v=jTHvFGjy5uA&list=PLH1HFavas54e0-05vZcZ0wNGhnpRyFmLc> (Retrieved 03/10/2015).
- [Bak09] Jeroen Bakker. *The mystery of the blend
The blender file-format explained*. 2009. URL: http://www.atmind.nl/blender/mystery_ot_blend.html (Retrieved 03/10/2015).
- [Ble14b] Adam Kalisz (BlenderEi). *[C++/Qt]: Export .blend with procedurally generated mesh?* 2014. URL: <http://www.blenderartists.org/forum/showthread.php?362865-C-Qt-Export-blend-with-procedurally-generated-mesh> (Retrieved 11/03/2015).
- [Owe15] Owen Blacker. *Freedom of Panorama is under attack — Vantage — Medium*. 2015. URL: <https://medium.com/vantage/freedom-of-panorama-is-under-attack-6cc5353b4f65> (Retrieved 06/27/2015).
- [KJ12] Hans-Michael Körner and Bruno Jahn. *Große Bayerische Biographische Enzyklopädie*. Berlin: De Gruyter, 2012, p. 2128. URL: <http://www.degruyter.com/view/product/62595> (Retrieved 03/11/2015).
- [Sha13] ShareLaTeX. *Youtube: How to Write a Thesis in LATEX (parts 1 to 5)*. 2013. URL: <https://www.youtube.com/watch?v=gFAQd0ueIMc&index=1&list=PLCRFsOKSM7eNGNghvT6QdzsDYwSTZxqjC> (Retrieved 01/23/2015).
- [Vel15] Claudio Vellage. *LATEXTutorial – Interactive Lessons, Code Examples – For Beginners*. 2015. URL: <http://www.latex-tutorial.com/> (Retrieved 01/23/2015).