# Computer Vision
# ICP, EGC, SFM

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## Abstract

In this technical report we present the implementation together with results we obtained for three separate classes of algorithms. Section 1 introduces each of these algorithms, discussing also their aspects and applications. Section 2 presents the three dimensional point cloud registration technique called Iterative Closest Point[1] (ICP) algorithm. Structure of motion can be obtained through Epipolar geometry and chaining of invariant detected points [2]



## References

[1] Besl, Paul J., and Neil D. McKay. "Method for registration of 3-D shapes." In Robotics-DL tentative, pp. 586-606. International Society for Optics and Photonics, 1992.

[2] Rothganger, Fred, Svetlana Lazebnik, Cordelia Schmid, and Jean Ponce. "3d object modeling and recognition using local affine-invariant image descriptors and multi-view spatial constraints." International Journal of Computer Vision 66, no. 3 (2006): 231-259.