

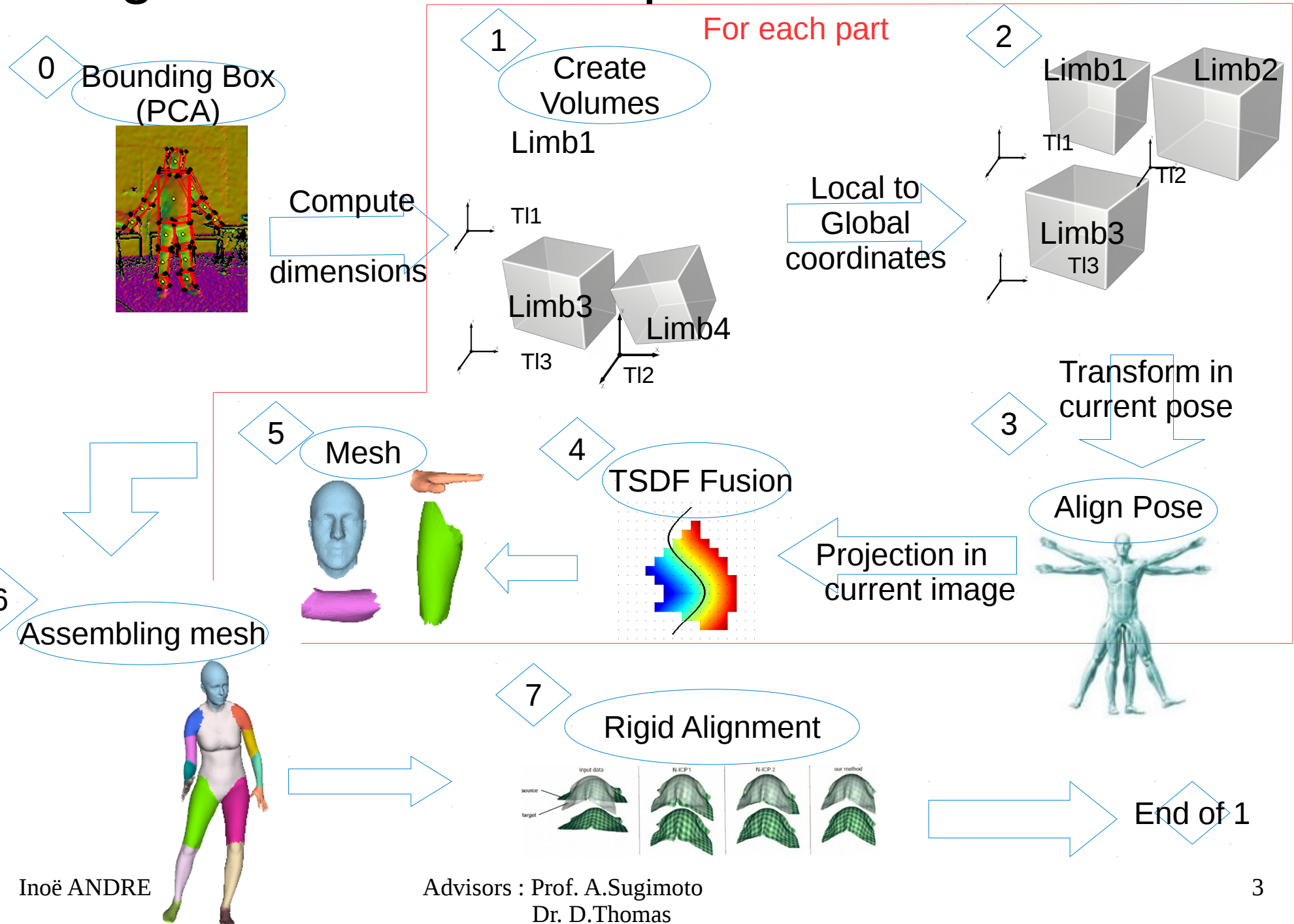
# Dynamic fusion

Internship Week 23  
Segmented Fusion  
27<sup>th</sup> July 2017

# Last meeting

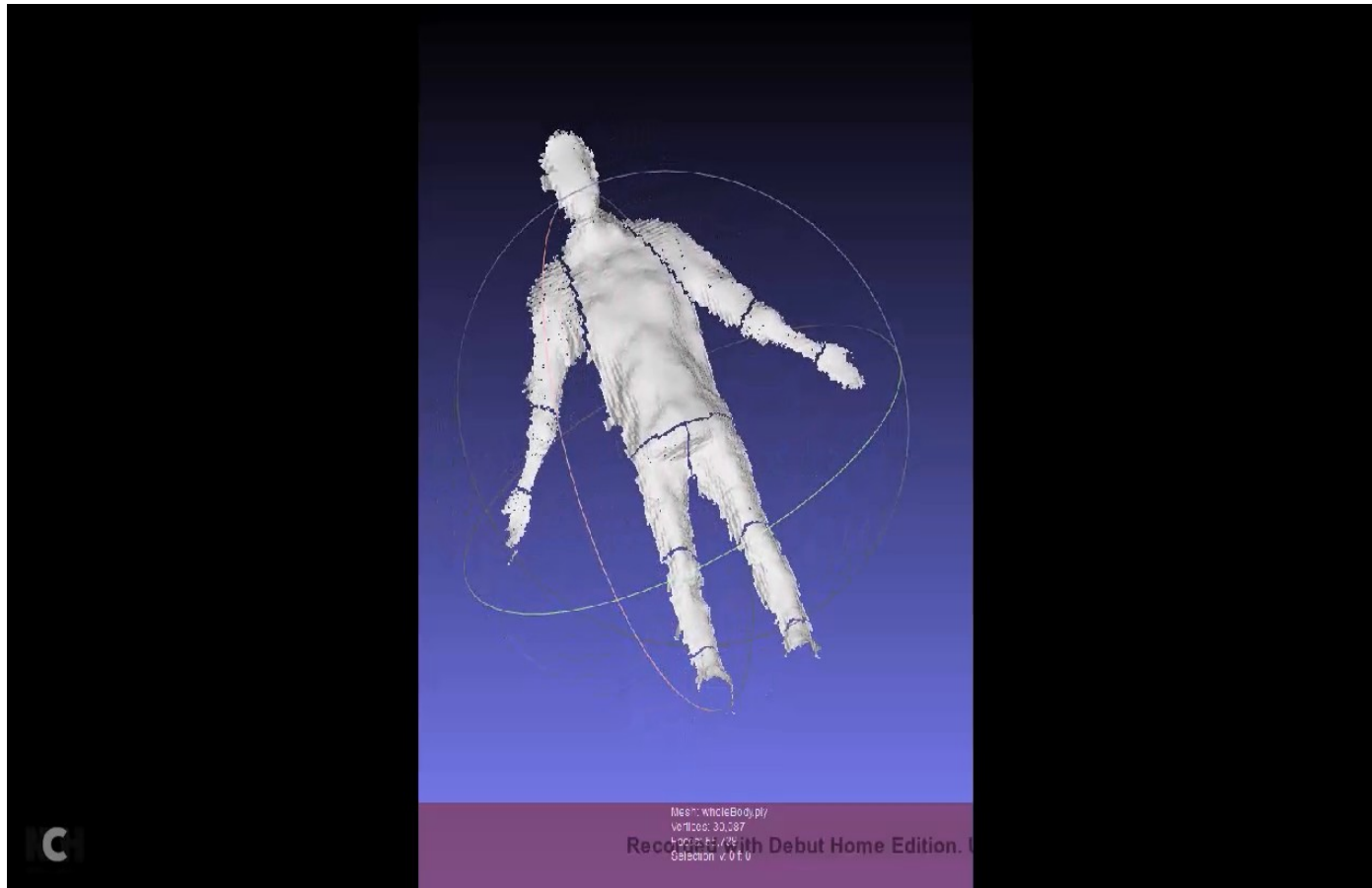
- Previously
  - Stitching Puppet algo
  - Volume and local to global transform
  - Segmented fusion
- Plan for today's meeting:
  - Correct part based fusion
  - Add distance constraint on adjacent part
  - Clear explanation of Stitching Puppet

# Segmented Fusion Pipeline



# Naive Stitching results

Stitching image 15

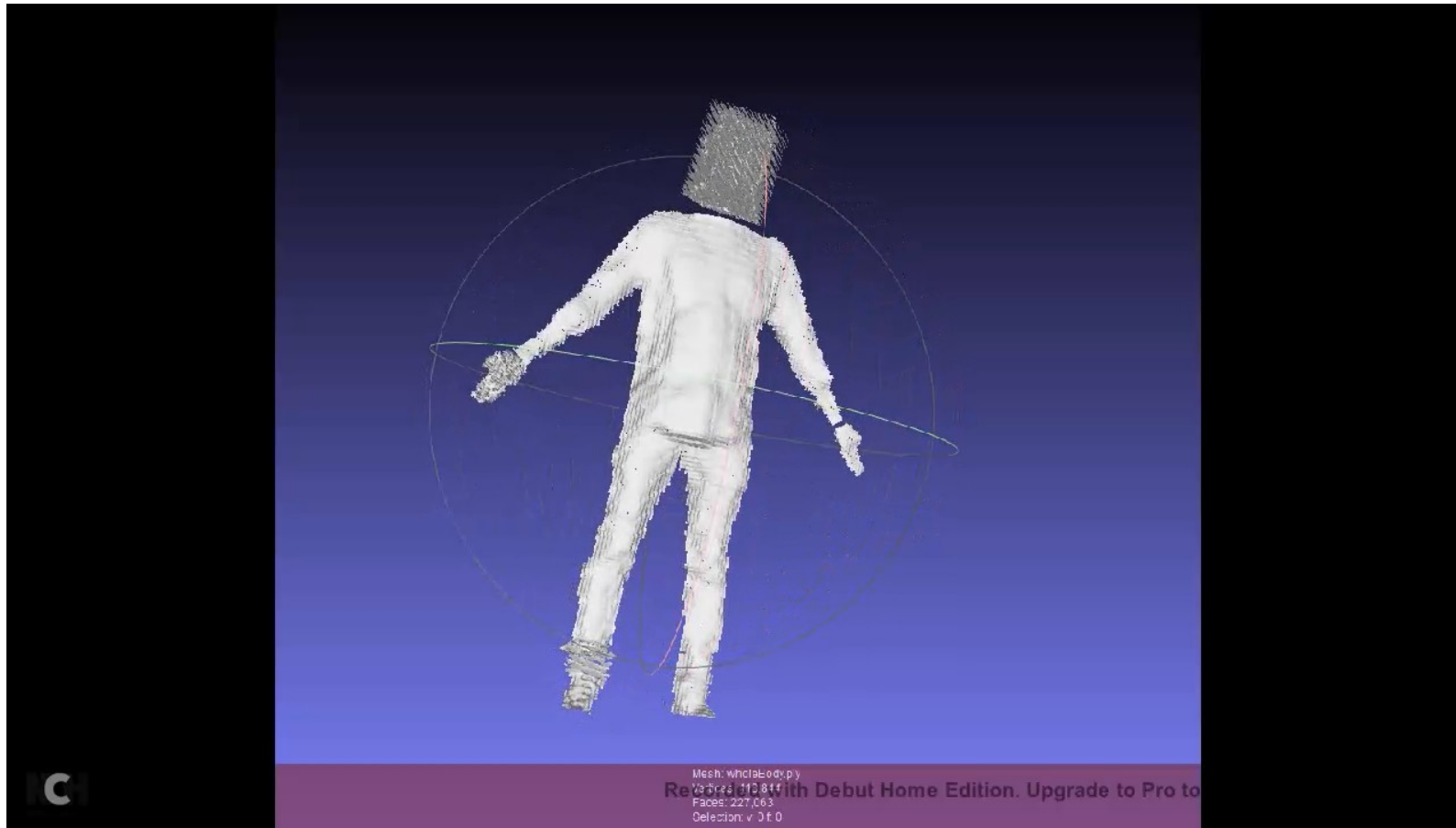


Depth map chopped too!

To Get the neck : make the bounding boxes longer of 5 voxels and do not separated head from torso in depth image

# Naive Stitching results

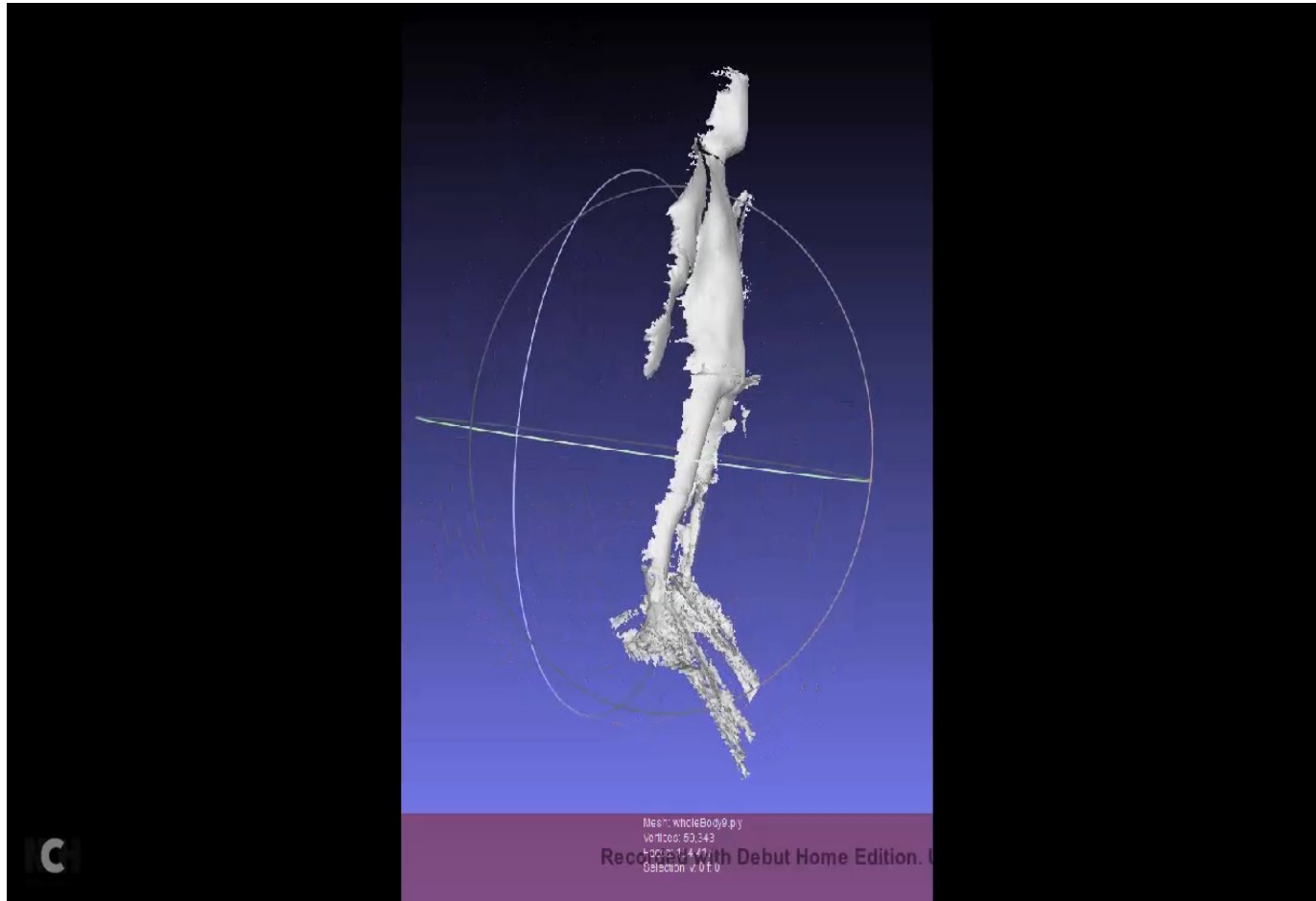
Last week bug



List of My\_MC  
object instead  
of overwriting it

# Segmented tracking results

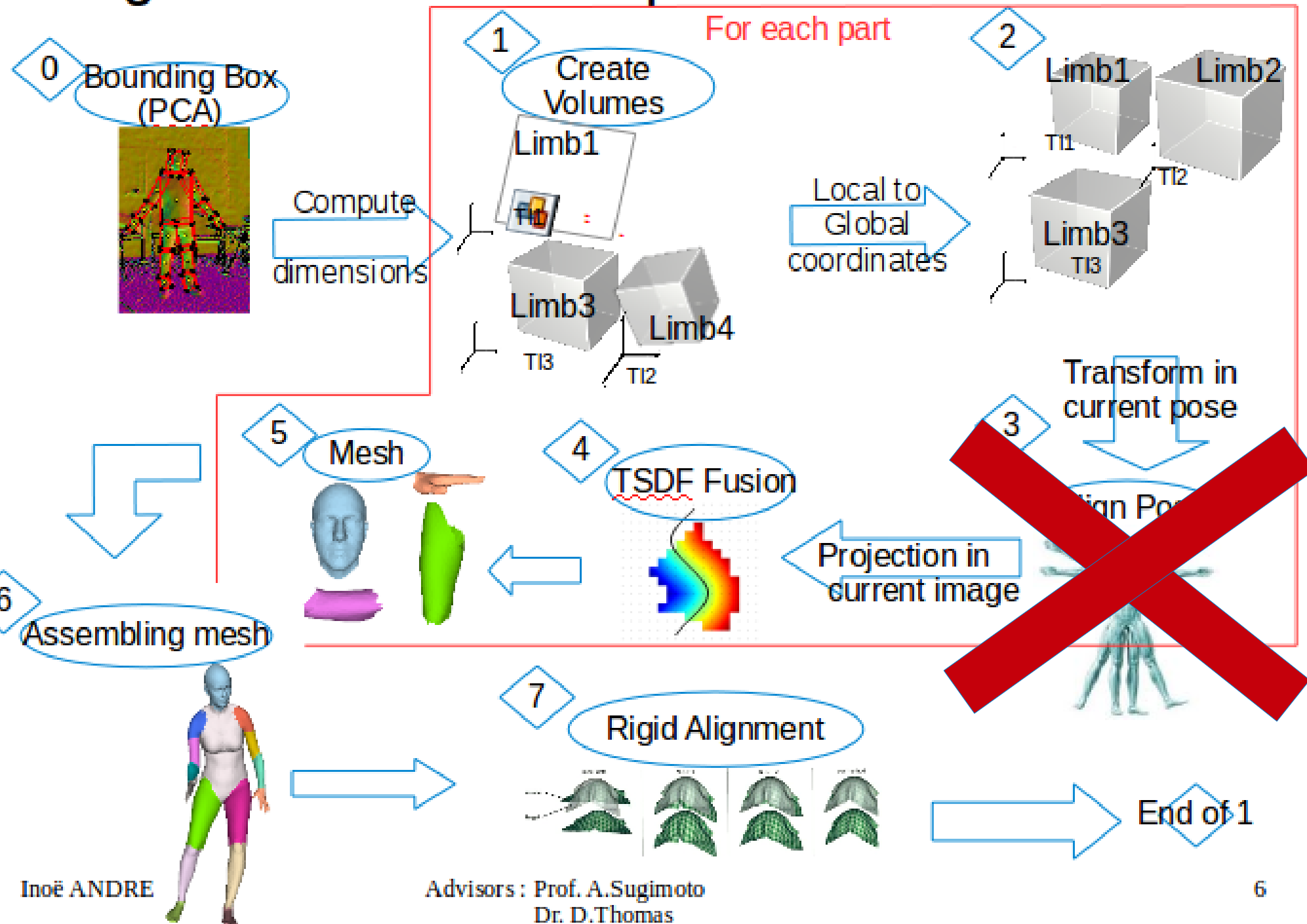
Tracking image 0-9



Last week : in pipeline  
Go back to 0 instead of end of  
1.

Inversed orientation  
 $T_{loc} \rightarrow glo$  of the current  
image used for former  
mesh  $\Rightarrow$  inversion

# Segmented Fusion Pipeline



# Segmented tracking results

Tracking image 0-9 using tracking on T\_loc → glo updated

Tracking  
error





# Segmented tracking results

Tracking image 0-9 using tracking on T\_loc → glo non updated

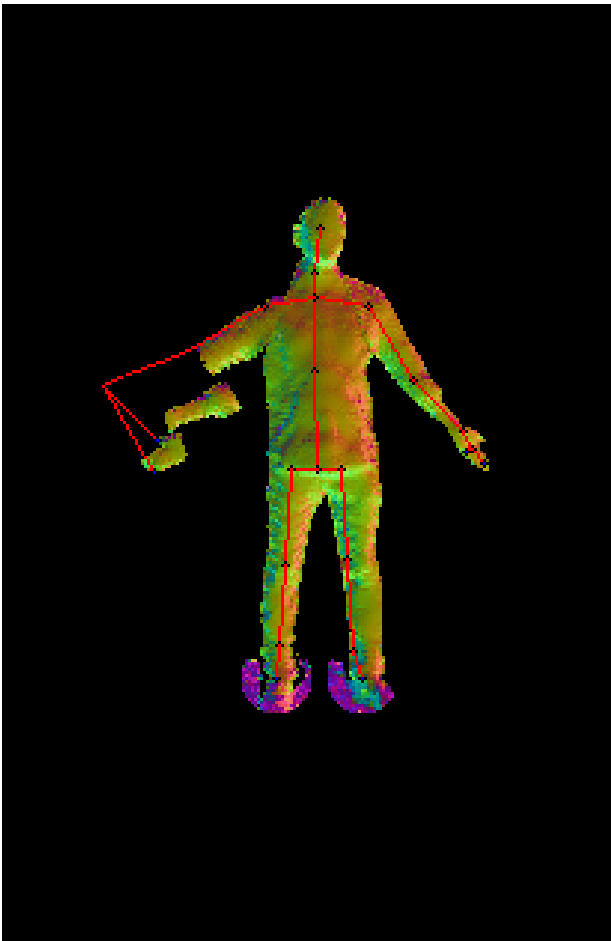


Still error in the tracking.  
Seems like duplicate

Tracking not adapted for each body part?

# Moving arm results

Nothing realist yet



```
angley = 0.5 # pi * 2. * delta_x / float(self.Size[0])
RotZ = np.array([[cos(angley), -sin(angley), 0.0, 0.0], \
                  [sin(angley),  cos(angley), 0.0, 0.0], \
                  [0.0,          0.0,      1.0, 0.0], \
                  [0.0,          0.0,      0.0, 1.0]])
```

# Dataset



# Action plan

- Segmented fusion
  - Alignment
- Report for NII
- Report for Grenoble INP
- Joints