**EN2550 Assignment 2 on Fitting and Alignment**

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GitHub Link: <https://github.com/KCSAbeywickrama/EN2550-Excercises/tree/master/Assignment_02>

Only important code parts & results have been included. Full code with all function implementation is on [GitHub](https://github.com/KCSAbeywickrama/EN2550-Excercises/tree/master/Assignment_02).

**1) (a)**

def get\_circle(points,max\_r):  # find circle from 3 points

    …

def fit\_circle(points):  # find the best circle from a set of points algebraically

    …

def get\_inliers(points,thres): # find inliers using RANSAC

    point\_count=len(points)

    max\_inlier\_count=0

    max\_r=(np.max(points)-np.min(points))/2

    for ittr in range(ittrs\_limit):

        init\_points=points[np.random.choice(point\_count,3)]

        circle=get\_circle(init\_points,max\_r)

        if(circle):

            center,r=circle

            tmp\_diff\_sqr=(points-np.array(center))\*\*2

            r\_difs=np.abs(np.sqrt(tmp\_diff\_sqr[:,0]+tmp\_diff\_sqr[:,1])-r)

            inliers = points[r\_difs<thres]

            inlier\_count=len(inliers)

            if inlier\_count>max\_inlier\_count:

                match\_circle,match\_samples,match\_inliers=circle,init\_points,inliers

                max\_inlier\_count=inlier\_count

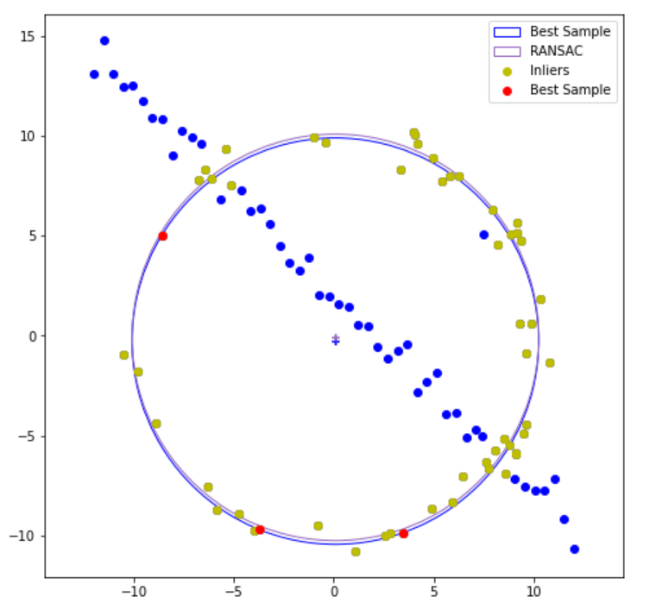
    return match\_circle,match\_samples,match\_inliers

ittrs\_limit=500

inlie\_thres=1

(smpl\_center,smpl\_r),smpl\_points,inliers=get\_inliers(X,inlie\_thres) #get inliers using RANSAC

ransac\_center,ransac\_r=fit\_circle(inliers) #find best circle from inliers using algebriacally



After getting the set of inliers, to get a better result the circle has been recalculated by considering all the inliers (removed function implementation available in the [notebook](https://github.com/KCSAbeywickrama/EN2550-Excercises/blob/master/Assignment_02/190018V_a02.ipynb) on [GitHub](https://github.com/KCSAbeywickrama/EN2550-Excercises/tree/master/Assignment_02))

**1) (b)**

There is a little difference between the circle from the best matching sample set & the recalculated circle by considering all inliers. The recalculated circle is more accurate because all inliers have been considered instead of considering only 3 sample points. (Clear large image is available in the [notebook](https://github.com/KCSAbeywickrama/EN2550-Excercises/blob/master/Assignment_02/190018V_a02.ipynb) on [GitHub](https://github.com/KCSAbeywickrama/EN2550-Excercises/tree/master/Assignment_02))

**2)**

img\_dst=cv.imread('imgs2/00x.jpg')

img\_src=cv.imread('imgs2/flagx.png')

points\_des=np.array(get\_points(img\_dst))

img\_src\_h=img\_src.shape[0]

img\_src\_w=img\_src.shape[1]

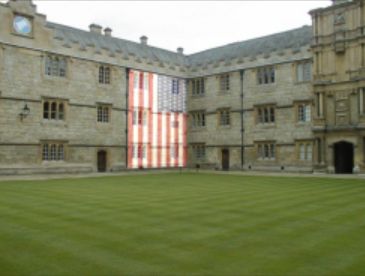
points\_src=np.array([(0,0),(img\_src\_w,0),(img\_src\_w,img\_src\_h),(0,img\_src\_h)])

h,st=cv.findHomography(points\_src,points\_des)

img\_warp=cv.warpPerspective(img\_src,h,img\_dst.shape[1::-1])

img\_out=cv.addWeighted(img\_warp,0.5,img\_dst,1,0.0)

get\_points() is a function that uses GUI options in OpenCV to find destination points of the flag image in the architectural image with mouse clicks (implementation available in the notebook on GitHub). Computing homography, warping & superimposing has done using inbuilt functions in OpenCV.

Images with flat surfaces (large walls) have been selected as architectural images. Since flags are flat superimposing these into flat surfaces on the architectural images ends up with a nice result.

A wall covered in graffiti

Description automatically generated with low confidence**3) (a)**

img1=cv.imread('imgs3/img1.ppm')

img2=cv.imread('imgs3/img4.ppm')

sift=cv.SIFT\_create()

kp1,des1=sift.detectAndCompute(img1,None)

kp2,des2=sift.detectAndCompute(img2,None)

bf=cv.BFMatcher()

matches=bf.knnMatch(des1,des2,k=2)

good=[];pts1=[];pts2=[]

for m,n in matches:

    if m.distance<0.65\*n.distance:

        pts1.append(kp1[m.queryIdx].pt);pts2.append(kp2[m.trainIdx].pt);good.append([m])

img\_match=cv.drawMatchesKnn(img1,kp1,img2,kp2,good,None,flags=2)

Since the projective angle between img1 & img5 is very high it is very difficult to find a reasonable amount of matching features using SIFT. Because SIFT does not perform well in large changes in viewpoint angle. So img1 & img4 have been selected to continue the question workout. (workout of trying to match SIFT features between img1 & img5 has been included in [GitHub](https://github.com/KCSAbeywickrama/EN2550-Excercises/tree/master/Assignment_02) for the completion. But by limiting points to best points by reducing the threshold and then manually checking it can be seen that those are incorrect matches)

**3) (b)**

def compute\_H(pts1,pts2):

    A=[]

    for i in range(len(pts1)):

        xs,ys=pts1[i]

        xd,yd=pts2[i]

        A.append((xs,ys,1,0,0,0,-xd\*xs,-xd\*ys,-xd))

        A.append((0,0,0,xs,ys,1,-yd\*xs,-yd\*ys,-yd))

    A=np.array(A)

    L,V=np.linalg.eig(A.T @ A)

    l=np.argmin(np.abs(L))

    v=V[:,l]

    h33=v[-1]

    return v.reshape((3,3))/h33

max\_inlier\_count=0

for n in range(5000):

    smpl\_indxs=np.random.choice(len(pts1),4,replace=False)

    smpl\_pts1=pts1[smpl\_indxs]

    smpl\_pts2=pts2[smpl\_indxs]

    H=compute\_H(smpl\_pts1,smpl\_pts2)

    Xs=np.vstack((pts1.T,np.ones(pts1.shape[0],dtype=int)))

    Xd=pts2.T

    XdH=H @ Xs

    XdH=XdH/XdH[2]

    XdH=np.delete(XdH,2,axis=0)

    tmp\_diff\_sqr=(XdH-Xd)\*\*2

    dis\_diff=np.sqrt(tmp\_diff\_sqr[0]+tmp\_diff\_sqr[1])

    thres=2

    inlier\_idxs=dis\_diff<thres

    inliers=pts1[inlier\_idxs],pts2[inlier\_idxs]

    inlier\_count=len(inliers[0])

    if(inlier\_count>max\_inlier\_count):

        match\_inliers=inliers

        max\_inlier\_count=inlier\_count

H=compute\_H(\*match\_inliers)

H=

[[ 6.56816848e-01 6.80640096e-01 -3.08528938e+01]

[-1.51582999e-01 9.69920508e-01 1.49997446e+02]

[ 4.09138545e-04 -1.06392211e-05 1.00000000e+00]]

the square root of sum of squared differences between calculated H & given H in the data set is **1.280**

Above Homography(H) computation is for img1 & img4. Due to the issue mentioned in 3 (a) can’t calculate H between img1 & img5 only using SIFT matches directly. But applying the above same procedure to img1 & img3 and then img3 & img5, H1to3 & H3to5 can be obtained. Then using,

    H1to5= H3to5 @ H1to3

relationship, H1to5 can be calculated.

the square root of sum of squared differences between calculated H1to5 & given H1to5 in the data set is **1.881**

So calculated Homograpies and given Homograpies are almost equal. So Homography calculation is very accurate. ( Reading given H and the calculating differences & rest of the code is available in the [notebook](https://github.com/KCSAbeywickrama/EN2550-Excercises/blob/master/Assignment_02/190018V_a02.ipynb) on [GitHub](https://github.com/KCSAbeywickrama/EN2550-Excercises/tree/master/Assignment_02))

**3) (c)**

T=np.array([[1,0,50],[0,1,50],[0,0,1]],dtype=float)

img1\_mask=np.ones(img1.shape)

canvas1=cv.warpPerspective(img1,T @ H1to5,(900, 850))

canvas1\_mask=cv.warpPerspective(img1\_mask,T @ H1to5,(900, 850))==1

canvas5=cv.warpPerspective(img5,T,(900, 850))

canvas\_out=np.array(canvas5)

canvas\_out[canvas1\_mask]=canvas1[canvas1\_mask]

A picture containing text

Description automatically generated A picture containing text

Description automatically generated A picture containing text, different

Description automatically generated

Translation(using T matrix) has been given to img1 & img5 for better results without cropping parts after stitching. Translation & projection has given to img1 at once by multiplying the Translation matrix and Homography. Mask of warped img1 has been used to place warped img1 on top of img5.