Making Figures for CVPR paper

Figure 16 (same process for figure 13 but use different data)

load('ResultsX10.mat')

load('ResultsX5.mat')

load('ResultsX2\_5.mat')

load('ResultsX1\_25.mat')

xAxisLabel = [ -5, -3, -1, 0, -1, -3, -5]

figure

plot(xAxisLabel/30, x10)

hold all

plot(xAxisLabel/30, x5)

axis([-.15,.15,0,2.5])

title('Real Images - Coaxial Camera - RMS Disparity Error')

xlabel('dZ m/s')

ylabel('RMS Disparity Error (pixels)')

legend('dX = 0.3 m/s', 'dX = 0.15 m/s')

For Renderings

Initially use flow by importing flow.mat from 10mm x, 0mm z flow (directory 13)

Create GTS file by running uv2pc (for stereo this is in 2015\_10\_31\_Stereo), this gives me the variable in the workspace called pc which is a point cloud. Export the point cloud using exportPC.m in same directory. Rename the file pc.cvs to pc.gts and open with meshlab.

The following instructions come from: http://gmv.cast.uark.edu/scanning/point-clouds-to-mesh-in-meshlab/

Filter->Sampling->Poisson Disk Sampling, check Base Mesh Subsampling

Filters -> Point Set -> Compute Normals for point set

Filters -> Point Set-> Surface Reconstruction: Poisson