

CS4243's Project

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Outline

- 1 Introduction
- 2 Panorama Stitching
 - Extract SIFT features
 - Estimate homography with RANSAC
- 3 Object Tracking
 - Mean shift
 - Background Subtraction
- 4 Registration into 2D field Map
 - Estimate homography
 - Represent players into 2D map
 - Calculate the distance covered by each player

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- The features are invariant to image scale and rotation.
- provide robust matching across a substantial range of affine distortion, change in 3D viewpoint, addition of noise, and change in illumination.
- Matching feature descriptors between two using a fast nearest-neighbor algorithm.

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- **RANSAC** algorithm is used to perform robust homography estimation.
- Warp the source frame (right or left view) using the robust estimated homography matrix.
- Align the resultant source frame(warped left or right frame) with destination image(mid view frame), using color averaging.

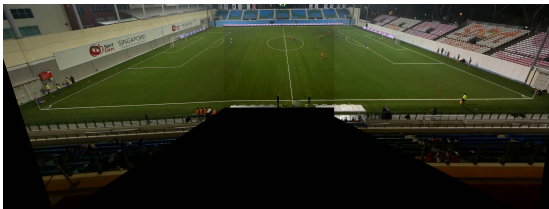


Figure 1: Normal Alignment

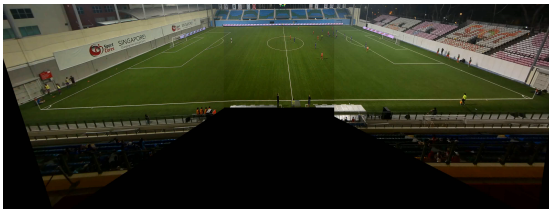


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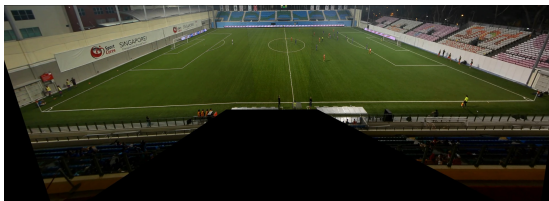


Figure 2: Color Averaging Alignment

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- Mean shift is an algorithm that iteratively shifts a data point to the average of data points in its neighborhood.
- Similar to clustering.
- Add a mask that ranges the desired color pixels using **HSV** color space.
- Move accordingly the center of mean shift's window to highest density of desired pixels.

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- Apply the background subtraction method we learned in the class on 3 channels.

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- The output of our method generates a video contains colored moving objects(foreground) with black background.
- The normal video and the background subtraction video used alternatively to track objects with a mean shift.

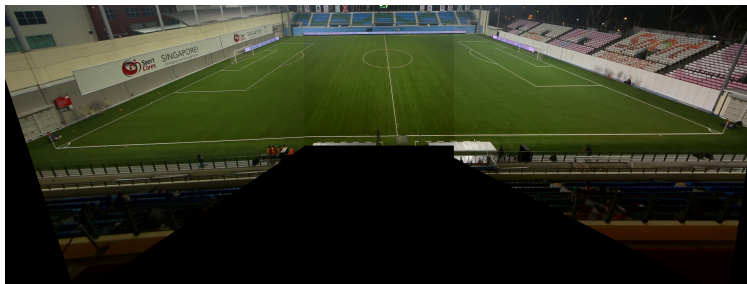


Figure 3: Empty field after subtracting the foreground

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- Match by hand the corresponding corner points between the real stitched field and standard field map, and estimate homography for 31 corresponding corner points.

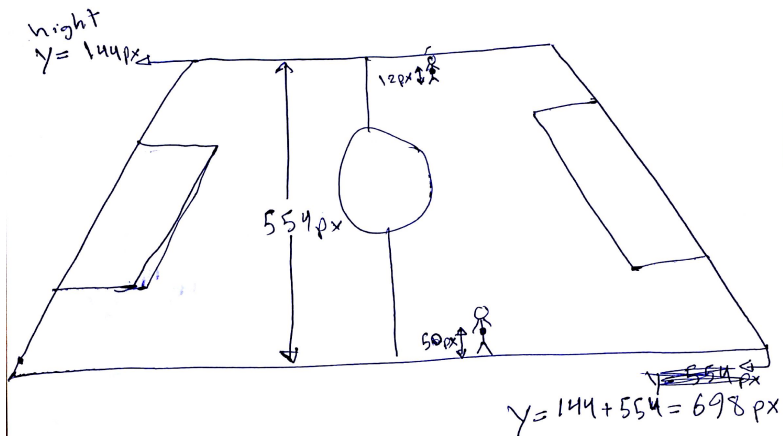
- Match by hand the corresponding corner points between the real stitched field and standard field map, and estimate homography for 31 corresponding corner points.



Figure 4: Match the red points, which are show the corresponding corner points

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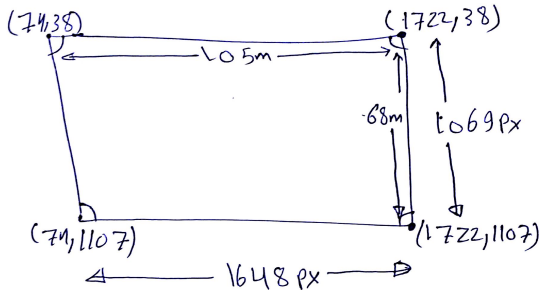


$$y = y + \text{int}(((y - 144.00) / 554.00) * 38 + 12)$$

\hookrightarrow offset
 $\hookrightarrow (50 - 12) \text{ ratio}$
 $\hookrightarrow (698 - 144) \text{ ratio}$

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Standard pitch measurement. Not all pitches are the same size, though. The preferred size for many professional team's stadiums is 105 by 68 metres.

$$\begin{array}{lcl} 105\text{m} & \longrightarrow & 1648\text{px} \\ 68\text{m} & \longrightarrow & 1069\text{px} \end{array} \quad \left| \quad \begin{array}{lcl} 10500\text{cm} & \longrightarrow & 1648\text{px} \\ 6800\text{cm} & \longrightarrow & 1069\text{px} \end{array}$$

$$10500/1648 = 6.37 \text{ cm/px}$$

$$6800/1069 = 6.36 \text{ cm/px}$$

Conclusion

- Build a **python code from scratch**.
- Stitch a **dynamic panorama** taken from three different cameras.
- Track players along five minutes.
- Register the players into 2D map.
 - Analysis of total overall distances covered in a match.
 - Build the entry point to analyze the soccer match.

References I



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