Desription of solution

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GitHub repository with solution

1. In function *get_view* the new CameraPose class object (pose_i) with extrinsics matrix for image_i was created. Also, the new RaycastingImaging class object (imaging_i) with image resolution and resolution_3d from intrinsics dictionary for image_i was created. To get point cloud from depth image function image_to_points from imaging_i was used. To transform the image to points in world frame camera_to_world function from pose_i was used. So, points_i from depth image_i in world frame was constructed.

2. In function *pairwise_interpolate_predictions* to be able to interpolate in view_i points from view_j were reprojected to view_i. For reprojection function world_to_camera from camera pose_i was used. So reprojected_j was got.

3. Then we found k (nn_set_size) nearest points for each of the points from reprojected_j. This point was from view_i. So indexes of these points(nn_indexes_in_i) were got.

4. Before building interpolation, we need to check the possibility of it. Firstly, for points_i in the pixel grid of view_i with indexes (point_nn_indexes) that was got from nn_indexes_in_i we created an array. This array was consists of X and Y coordinates of this point and Z coordinate that was from image_i. So we got point_from_j_nns. Secondly, we found a distance between this point and point_from_j. If this distance less than a particular threshold the interpolation is possible.

5. If interpolation is possible, we made a bilinear interpolator from distances predicted in view_i (distances_i) into the point in view_j. For this, we can use interpolate.interp2d function from scipy. But it is not

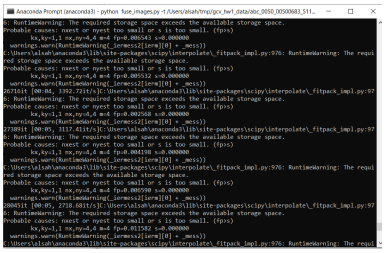

Figure 1: interp2d

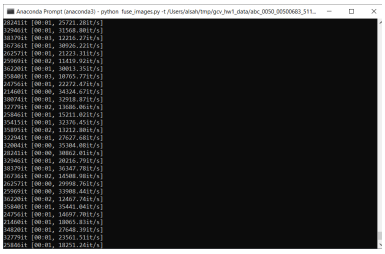

Figure 2: bisplrep and bisplev

stable 1. For stable interpolation, we can use interpolate.bisplrep and interpolate.bisplev from scipy 2.

All changes were made in files *repo/gcv_v20211_hw1/fusion/interpolators* with unstable interpolator and *repo/gcv_v20211_hw1/fusion/interpolators_s* with stable interpolator. Also, in notebook *repo/notebooks/gcv_v20211_hw1.ipynb* some results are perfomed.