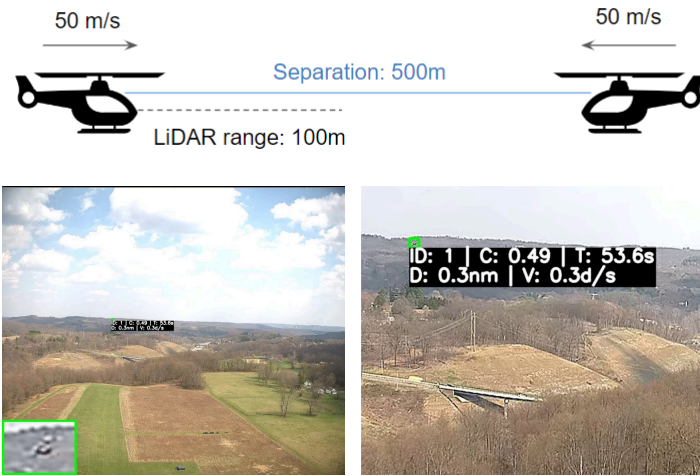


Multi-Camera Object Track Fusion for Visual Detect and Avoid (DAA)

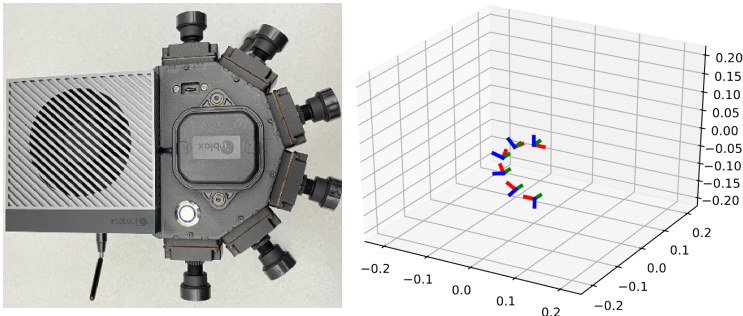
Nikhil Keetha

Detect and Avoid (DAA)



Multi-Camera Setup and Calibration

➤ Intrinsic & Pair-wise Extrinsic Calibration

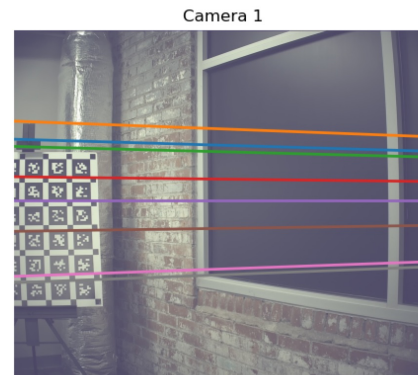
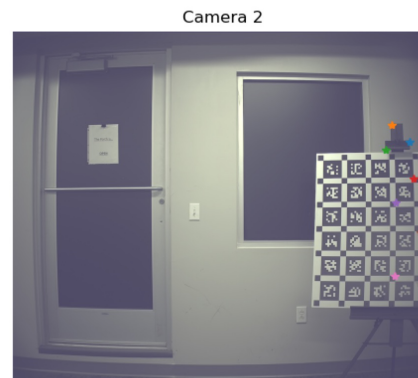


Epipolar Geometry

$$P = K \begin{bmatrix} I & 0 \end{bmatrix}$$

$$P' = K' \begin{bmatrix} R & t \end{bmatrix}$$

$$F = K'^{-T} R K^T [K R^T t]_x$$



Results: Intruder Re-ID

