In [3]:

```
!pip install torchsummary
```

```
Collecting torchsummary
  Downloading torchsummary-1.5.1-py3-none-any.whl (2.8 kB)
Installing collected packages: torchsummary
Successfully installed torchsummary-1.5.1
```

In [4]:

```
import numpy as np

import scipy.io
import os
from numpy.linalg import norm,det,inv,svd
from scipy.linalg import rq
import math
import matplotlib.pyplot as plt
import numpy as np
import math
import random
import sys
from scipy import ndimage,spatial
from tqdm.notebook import trange,tqdm
import torch
import torch.nn as nn
import torch.optim as optim
from torch.optim import lr_scheduler
from torch.autograd import Variable
import torchvision
from torchvision import datasets,models,transforms
from  torch.utils.data import Dataset,DataLoader,ConcatDataset
from skimage import io,transform,data
from torchvision import transforms,utils
import  os
import sklearn.svm
import cv2
from os.path import exists
import pandas as pd
import PIL
from sklearn.metrics.cluster import completeness_score
from sklearn.cluster import KMeans
from tqdm import tqdm,tqdm_notebook
from functools import partial
from  torchsummary import summary
from torchvision.datasets import ImageFolder
from torch.utils.data.sampler import SubsetRandomSampler
```

In [5]:

```
class Image:
    def __init__(self,img,position):
        self.img = img
        self.position  = position

inliner_matchset = []
def features_matching(a,keypointlength,threshold):
    bestmatch = np.empty((keypointlength), dtype=np.int16)
    img1index = np.empty((keypointlength),dtype=np.init16)
    distance = np.empty((keypointlength))
    index =0
    for j in range(0,keypointlength):
        x=a[j]
        listx = x.tolist()
        x.sort()
        minval1=x[0]
        minval2=x[1]
        itemindex1 = listx.index(minval1)
        itemindex2 = listx.index(minval2)
        ratio = minval1/minval2

        if ratio < threshold:
            bestmatch[index] = itemindex1
            distance[index] = minval1
            img1index[index] = j
            index = index + 1
    return [cv2.DMatch(img1index[i],bestmatch[i].astype(int),distance[i]) for i in range
(0,index)]

def compute_Hmography(im1_pts,im2_pts):
    num_matches=len(im1_pts)
    num_rows = 2*num_matches
    num_cols = 9
    A_matrix_shape = (num_rows,num_cols)
    A = np.zeros(A_matrix_shape)
    a_index = 0
    for i in range(0,num_matches):
        (a_x,a_y) = im1_pts[i]
        (b_x,b_y) = im2_pts[i]
        row1 = [a_x,a_y,1,0,0,0,-b_x*a_x,-b_x*a_y,-b_x]
        row2 = [0,0,0,a_x,a_y,1,-b_y*a_x,-b_y*a_y,-b_y]
        A[a_index] = row1

        A[a_index+1] = row2
        a_index += 2

    U,s,Vt = np.linalg.svd(A)
    H = np.eye(3)
    H = Vt[-1].reshape(3,3)
    return H

def displayplot(img,title):
    plt.figure(figsize=(15,15))
    plt.title(title)
    plt.imshow(cv2.cvtColor(img,cv2.COLOR_BGR2RGB))
    plt.show()

def RANSAC_alg(f1,f2,matches,nRANSAC,RANSACthresh):
    minMatches = 4
    nBest = 0
    best_inliners = []
    H_estimate = np.eye(3,3)
    global inliner_matchset
    inliner_matchset = []
    for iteration in range(nRANSAC):
        matchSimple = random.sample(matches,minMatches)
        im1_pts = np.empty((minMatches,2))
        im2_pts = np.empty((minMatches,2))
        for i in range(0,minMatches):
            m  = matchSimple[i]
            im1_pts[i] = f1[m.queryIdx].pt
            im2_pts[i] = f2[m.trainIdx].pt

        H_estimate = compute_Hmography(im1_pts,im2_pts)
        inliners = get_inliners(f1,f2,matches,H_estimate,RANSACthresh)
        if len(inliners) > nBest:
            nBest = len(inliners)
            best_inliners= inliners

    print("Number of best inliners", len(best_inliners))
    for i in range(len(best_inliners)):
        inliner_matchset.append(matches[best_inliners[i]])
    im1_pts = np.empty((len(best_inliners),2))
    im2_pts = np.empty((len(best_inliners),2))
    for i in range(0,len(best_inliners)):
        m = inliner_matchset[i]
        im1_pts[i] = f1[m.queryIdx].pt
        im2_pts[i] = f2[m.trainIdx].pt
    M = compute_Hmography(im1_pts,im2_pts)
    return M, len(best_inliners)
```

In [1]:

```
!pip install opencv-python==3.4.2.17
!pip install opencv-contrib-python==3.4.2.17
```

```
Collecting opencv-python==3.4.2.17
  Downloading opencv_python-3.4.2.17-cp37-cp37m-manylinux1_x86_64.whl (25.0 MB)
     |████████████████████████████████| 25.0 MB 15.1 MB/s eta 0:00:01
Requirement already satisfied: numpy>=1.14.5 in /opt/conda/lib/python3.7/site-packages (f
rom opencv-python==3.4.2.17) (1.19.5)
Installing collected packages: opencv-python
  Attempting uninstall: opencv-python
    Found existing installation: opencv-python 4.5.1.48
    Uninstalling opencv-python-4.5.1.48:
      Successfully uninstalled opencv-python-4.5.1.48
Successfully installed opencv-python-3.4.2.17
Collecting opencv-contrib-python==3.4.2.17
  Downloading opencv_contrib_python-3.4.2.17-cp37-cp37m-manylinux1_x86_64.whl (30.6 MB)
     |████████████████████████████████| 30.6 MB 18.0 MB/s eta 0:00:01
Requirement already satisfied: numpy>=1.14.5 in /opt/conda/lib/python3.7/site-packages (f
rom opencv-contrib-python==3.4.2.17) (1.19.5)
Installing collected packages: opencv-contrib-python
Successfully installed opencv-contrib-python-3.4.2.17
```

In [2]:

```
import cv2
ast = cv2.FastFeatureDetector_create(10,True)
```

In [6]:

```
files_all = os.listdir('../input/uni-campus-dataset/RGB-img/img/')
files_all.sort()

folder_path = '../input/uni-campus-dataset/RGB-img/img/'
left_files_path_rev = []
right_files_path = []
for file in files_all[:61]:
    left_files_path_rev.append(folder_path + file)


left_files_path = left_files_path_rev[::-1]


for file in files_all[60:100]:
    right_files_path.append(folder_path + file)
```

In [7]:

```
gridsize = 6
clahe = cv2.createCLAHE(clipLimit=2.0,tileGridSize=(gridsize,gridsize))
images_left_bgr = []
images_right_bgr = []
images_left = []
images_right = []


for file in tqdm(left_files_path):
    left_image_sat= cv2.imread(file)
    lab = cv2.cvtColor(left_image_sat, cv2.COLOR_BGR2LAB)
    lab[...,0] = clahe.apply(lab[...,0])
    left_image_sat = cv2.cvtColor(lab, cv2.COLOR_LAB2BGR)
    left_img = cv2.resize(left_image_sat,None,fx=0.30, fy=0.30, interpolation = cv2.INTE
R_AREA)
    images_left.append(cv2.cvtColor(left_img, cv2.COLOR_BGR2GRAY).astype('float32')/255.)
    images_left_bgr.append(left_img)


for file in tqdm(right_files_path):
    right_image_sat= cv2.imread(file)
    lab = cv2.cvtColor(right_image_sat, cv2.COLOR_BGR2LAB)
    lab[...,0] = clahe.apply(lab[...,0])
    right_image_sat = cv2.cvtColor(lab, cv2.COLOR_LAB2BGR)
    right_img = cv2.resize(right_image_sat,None,fx=0.30,fy=0.30, interpolation = cv2.INT
ER_AREA)
    images_right.append(cv2.cvtColor(right_img, cv2.COLOR_BGR2GRAY).astype('float32')/255
.)
    images_right_bgr.append(right_img)
```

```
100%|██████████| 61/61 [00:55<00:00,  1.11it/s]
100%|██████████| 40/40 [00:35<00:00,  1.13it/s]
```

In [8]:

```
images_left_bgr_no_enhance = []
images_right_bgr_no_enhance = []

for file in tqdm(left_files_path):
    left_image_sat= cv2.imread(file)
    left_img = cv2.resize(left_image_sat,None,fx=0.30, fy=0.30, interpolation = cv2.INTE
R_AREA)
    images_left_bgr_no_enhance.append(left_img)

for file in tqdm(right_files_path):
    right_image_sat= cv2.imread(file)
    right_img = cv2.resize(right_image_sat,None,fx=0.30,fy=0.30, interpolation = cv2.INT
ER_AREA)
    images_right_bgr_no_enhance.append(right_img)
```

```
100%|██████████| 61/61 [00:27<00:00,  2.23it/s]
100%|██████████| 40/40 [00:17<00:00,  2.27it/s]
```

In [ ]:

```
Threshl=60;
Octaves=6;
#PatternScales=1.0f;
brisk = cv2.BRISK_create(Threshl,Octaves)

keypoints_all_left_brisk = []
descriptors_all_left_brisk = []
points_all_left_brisk=[]


keypoints_all_right_brisk = []
descriptors_all_right_brisk = []
points_all_right_brisk=[]


for imgs in tqdm(images_left_bgr):
    kpt = brisk.detect(imgs,None)
    kpt,descrip = brisk.compute(imgs, kpt)
    keypoints_all_left_brisk.append(kpt)
    descriptors_all_left_brisk.append(descrip)
    points_all_left_brisk.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr):
    kpt = brisk.detect(imgs,None)
    kpt,descrip = brisk.compute(imgs, kpt)
    keypoints_all_right_brisk.append(kpt)
    descriptors_all_right_brisk.append(descrip)
    points_all_right_brisk.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
orb = cv2.ORB_create(5000)
keypoints_all_left_orb = []
descriptors_all_left_orb = []
points_all_left_orb=[]
```

```
keypoints_all_right_orb = []
descriptors_all_right_orb = []
points_all_right_orb=[]

for imgs in tqdm(images_left_bgr_no_enhance):
    kpt = orb.detect(imgs,None)
    kpt,descrip = orb.compute(imgs, kpt)
    keypoints_all_left_orb.append(kpt)
    descriptors_all_left_orb.append(descrip)
    points_all_left_orb.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr_no_enhance):
    kpt = orb.detect(imgs,None)
    kpt,descrip = orb.compute(imgs, kpt)
    keypoints_all_right_orb.append(kpt)
    descriptors_all_right_orb.append(descrip)
    points_all_right_orb.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
kaze = cv2.KAZE_create(extended = True, threshold = 0.05)
keypoints_all_left_kaze = []
descriptors_all_left_kaze = []
points_all_left_kaze=[]

keypoints_all_right_kaze = []
descriptors_all_right_kaze = []
points_all_right_kaze=[]

for imgs in tqdm(images_left_bgr):
    kpt = kaze.detect(imgs,None)
    kpt,descrip = kaze.compute(imgs, kpt)
    keypoints_all_left_kaze.append(kpt)
    descriptors_all_left_kaze.append(descrip)
    points_all_left_kaze.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr):
    kpt = kaze.detect(imgs,None)
    kpt,descrip = kaze.compute(imgs, kpt)
    keypoints_all_right_kaze.append(kpt)
    descriptors_all_right_kaze.append(descrip)
    points_all_right_kaze.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [9]:

```
tqdm = partial(tqdm, position=0, leave=True)
```

In [ ]:

```
akaze = cv2.AKAZE_create()
keypoints_all_left_akaze = []
descriptors_all_left_akaze = []
points_all_left_akaze=[]

keypoints_all_right_akaze = []
descriptors_all_right_akaze = []
points_all_right_akaze=[]

for imgs in tqdm(images_left_bgr):
    kpt = akaze.detect(imgs,None)
    kpt,descrip = akaze.compute(imgs, kpt)
    keypoints_all_left_akaze.append(kpt)
    descriptors_all_left_akaze.append(descrip)
    points_all_left_akaze.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
for imgs in tqdm(images_right_bgr):
    kpt = akaze.detect(imgs,None)
    kpt,descrip = akaze.compute(imgs, kpt)
    keypoints_all_right_akaze.append(kpt)
    descriptors_all_right_akaze.append(descrip)
    points_all_right_akaze.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
star = cv2.xfeatures2d.StarDetector_create()
brief = cv2.xfeatures2d.BriefDescriptorExtractor_create()
keypoints_all_left_star = []
descriptors_all_left_brief = []
points_all_left_star=[]


keypoints_all_right_star = []
descriptors_all_right_brief = []
points_all_right_star=[]

for imgs in tqdm(images_left_bgr):
    kpt = star.detect(imgs,None)
    kpt,descrip = brief.compute(imgs, kpt)
    keypoints_all_left_star.append(kpt)
    descriptors_all_left_brief.append(descrip)
    points_all_left_star.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr):
    kpt = star.detect(imgs,None)
    kpt,descrip = brief.compute(imgs, kpt)
    keypoints_all_right_star.append(kpt)
    descriptors_all_right_brief.append(descrip)
    points_all_right_star.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
Threshl=60;
Octaves=8;
#PatternScales=1.0f;
brisk = cv2.BRISK_create(Threshl,Octaves)
freak = cv2.xfeatures2d.FREAK_create()
keypoints_all_left_freak = []
descriptors_all_left_freak = []
points_all_left_freak=[]


keypoints_all_right_freak = []
descriptors_all_right_freak = []
points_all_right_freak=[]

for imgs in tqdm(images_left_bgr):
    kpt = brisk.detect(imgs)
    kpt,descrip = freak.compute(imgs, kpt)
    keypoints_all_left_freak.append(kpt)
    descriptors_all_left_freak.append(descrip)
    points_all_left_freak.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr):
    kpt = brisk.detect(imgs,None)
    kpt,descrip = freak.compute(imgs, kpt)
    keypoints_all_right_freak.append(kpt)
    descriptors_all_right_freak.append(descrip)
    points_all_right_freak.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [12]:

```
mser = cv2.MSER_create(5,  70 ,500,  2.01)
sift = cv2.xfeatures2d.SIFT_create()
keypoints_all_left_mser = []
descriptors_all_left_mser = []
points_all_left_mser=[]

keypoints_all_right_mser = []
descriptors_all_right_mser = []
points_all_right_mser=[]
for imgs in tqdm(images_left_bgr_no_enhance):
    kpt = mser.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_left_mser.append(kpt)
    descriptors_all_left_mser.append(descrip)
    points_all_left_mser.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))


for imgs in tqdm(images_right_bgr_no_enhance):
    kpt = mser.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_right_mser.append(kpt)
    descriptors_all_right_mser.append(descrip)
    points_all_right_mser.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

```
100%|██████████| 61/61 [02:21<00:00,  2.32s/it]
100%|██████████| 40/40 [01:36<00:00,  2.41s/it]
```

In [ ]:

```
agast = cv2.AgastFeatureDetector_create()
sift = cv2.xfeatures2d.SIFT_create()
keypoints_all_left_agast = []
descriptors_all_left_agast = []
points_all_left_agast=[]

keypoints_all_right_agast = []
descriptors_all_right_agast = []
points_all_right_agast=[]


for imgs in tqdm(images_left_bgr):
    kpt = agast.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_left_agast.append(kpt)
    descriptors_all_left_agast.append(descrip)
    points_all_left_agast.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))


for imgs in tqdm(images_right_bgr):
    kpt = agast.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_right_agast.append(kpt)
    descriptors_all_right_agast.append(descrip)
    points_all_right_agast.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
fast = cv2.FastFeatureDetector_create(3,False)
sift = cv2.xfeatures2d.SIFT_create()
keypoints_all_left_fast = []
descriptors_all_left_fast = []
points_all_left_fast=[]

keypoints_all_right_fast = []
descriptors_all_right_fast = []
points_all_right_fast=[]
for imgs in tqdm(images_left_bgr_no_enhance):
    kpt = fast.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_left_fast.append(kpt)
    descriptors_all_left_fast.append(descrip)
    points_all_left_fast.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr_no_enhance):
    kpt = fast.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_right_fast.append(kpt)
    descriptors_all_right_fast.append(descrip)
    points_all_right_fast.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
fast = cv2.FastFeatureDetector_create(5)
```

```
sift = cv2.xfeatures2d.SIFT_create()
keypoints_all_left_fast = []
descriptors_all_left_fast = []
points_all_left_fast=[]

keypoints_all_right_fast = []
descriptors_all_right_fast = []
points_all_right_fast=[]
for imgs in tqdm(images_left_bgr_no_enhance):
    kpt = fast.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_left_fast.append(kpt)
    descriptors_all_left_fast.append(descrip)
    points_all_left_fast.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr_no_enhance):
    kpt = fast.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_right_fast.append(kpt)
    descriptors_all_right_fast.append(descrip)
    points_all_right_fast.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
gftt = cv2.GFTTDetector_create(qualityLevel = 0.07,useHarrisDetector=True,)
sift = cv2.xfeatures2d.SIFT_create()
keypoints_all_left_gftt = []
descriptors_all_left_gftt = []
points_all_left_gftt=[]

keypoints_all_right_gftt = []
descriptors_all_right_gftt = []
points_all_right_gftt=[]
for imgs in tqdm(images_left_bgr_no_enhance):
    kpt = gftt.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_left_gftt.append(kpt)
    descriptors_all_left_gftt.append(descrip)
    points_all_left_gftt.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr_no_enhance):
    kpt = gftt.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_right_gftt.append(kpt)
    descriptors_all_right_gftt.append(descrip)
    points_all_right_gftt.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
gftt = cv2.GFTTDetector_create(maxCorners = 20,qualityLevel = 0.09,useHarrisDetector=Fal
se,k=0.06)
sift = cv2.xfeatures2d.SIFT_create()
keypoints_all_left_gftt = []
descriptors_all_left_gftt = []
points_all_left_gftt=[]

keypoints_all_right_gftt = []
descriptors_all_right_gftt = []
points_all_right_gftt=[]
for imgs in tqdm(images_left_bgr_no_enhance):
    kpt = gftt.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_left_gftt.append(kpt)
    descriptors_all_left_gftt.append(descrip)
    points_all_left_gftt.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr_no_enhance):
    kpt = gftt.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_right_gftt.append(kpt)
    descriptors_all_right_gftt.append(descrip)
    points_all_right_gftt.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
daisy = cv2.xfeatures2d.DAISY_create()
sift = cv2.xfeatures2d.SIFT_create()
keypoints_all_left_daisy = []
descriptors_all_left_daisy = []
points_all_left_daisy=[]

keypoints_all_right_daisy = []
descriptors_all_right_daisy = []
points_all_right_daisy=[]

for imgs in tqdm(images_left_bgr):
    kpt = sift.detect(imgs,None)
    kpt,descrip = daisy.compute(imgs, kpt)
    keypoints_all_left_daisy.append(kpt)
    descriptors_all_left_daisy.append(descrip)
    points_all_left_daisy.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr):
    kpt = sift.detect(imgs,None)
    kpt,descrip = daisy.compute(imgs, kpt)
    keypoints_all_right_daisy.append(kpt)
    descriptors_all_right_daisy.append(descrip)
    points_all_right_daisy.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
surf = cv2.xfeatures2d.SURF_create()
sift = cv2.xfeatures2d.SIFT_create()
keypoints_all_left_surfsift = []
descriptors_all_left_surfsift = []
points_all_left_surfsift=[]

keypoints_all_right_surfsift = []
descriptors_all_right_surfsift = []
points_all_right_surfsift=[]

for imgs in tqdm(images_left_bgr_no_enhance):
    kpt = surf.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_left_surfsift.append(kpt)
    descriptors_all_left_surfsift.append(descrip)
    points_all_left_surfsift.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr_no_enhance):
    kpt = surf.detect(imgs,None)

    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_right_surfsift.append(kpt)
    descriptors_all_right_surfsift.append(descrip)
    points_all_right_surfsift.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
sift = cv2.xfeatures2d.SIFT_create(contrastThreshold=0.08,edgeThreshold=10,sigma=1.8)
keypoints_all_left_sift = []
descriptors_all_left_sift = []
points_all_left_sift=[]

keypoints_all_right_sift = []
descriptors_all_right_sift = []
points_all_right_sift=[]


for imgs in tqdm(images_left_bgr_no_enhance):
    kpt = sift.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_left_sift.append(kpt)
    descriptors_all_left_sift.append(descrip)
    points_all_left_sift.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr_no_enhance):
    kpt = sift.detect(imgs,None)
    kpt,descrip = sift.compute(imgs, kpt)
    keypoints_all_right_sift.append(kpt)
    descriptors_all_right_sift.append(descrip)
    points_all_right_sift.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [ ]:

```
surf = cv2.xfeatures2d.SURF_create()
keypoints_all_left_surf = []
descriptors_all_left_surf = []
points_all_left_surf=[]

keypoints_all_right_surf = []
descriptors_all_right_surf = []
points_all_right_surf=[]
for imgs in tqdm(images_left_bgr):
    kpt = surf.detect(imgs,None)
    kpt,descrip = surf.compute(imgs, kpt)
    keypoints_all_left_surf.append(kpt)
    descriptors_all_left_surf.append(descrip)
    points_all_left_surf.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))

for imgs in tqdm(images_right_bgr):
    kpt = surf.detect(imgs,None)
    kpt,descrip = surf.compute(imgs, kpt)
    keypoints_all_right_surf.append(kpt)
    descriptors_all_right_surf.append(descrip)
    points_all_right_surf.append(np.asarray([[p.pt[0],p.pt[1]] for p in kpt]))
```

In [ ]:

```
# sift  = cv2.xfeatures2d.SURF_Create()
# keypoints_all_left_surf = []
# descriptor_all_left_surf = []
# points_all_left_surf = []

# keypoints_all_right_surf = []
# descriptor_all_right_surf = []
# points_all_right_surf = []

#  for images in tqdm(left_images_bgr):
#  kpt = surf.detect(imgs,None)
# kpt, descrip = surf.compute(imgs,kpt)
# keypoints_all_left_surf.append(kpt)
#descriptor_all_left_surf.append(descrip)
#points_all_left_surf.append(np.asarray([[p.pt[0],p.pt[1]] for p in kpt])
#  points_all_left_surf.append(np.asarray([[p.pt[0], p.pt[1] for p in  kpt]]))
```

In [ ]:

```
class RootSIFT:
    def __init__(self):
        # initialize the SIFT feature extractor
        #self.extractor = cv2.DescriptorExtractor_create("SIFT")
        self.sift = cv2.xfeatures2d.SIFT_create()
    def compute(self, image, kps, eps=1e-7):
        # compute SIFT descriptors
        (kps, descs) = self.sift.compute(image, kps)
        # if there are no keypoints or descriptors, return an empty tuple
        if len(kps) == 0:
            return ([], None)
        # apply the Hellinger kernel by first L1-normalizing, taking the
        # square-root, and then L2-normalizing
        descs /= (np.linalg.norm(descs, axis=0, ord=2) + eps)
        descs /= (descs.sum(axis=0) + eps)
        descs = np.sqrt(descs)
        #descs /= (np.linalg.norm(descs, axis=0, ord=2) + eps)
        # return a tuple of the keypoints and descriptors
        return (kps, descs)
```

In [ ]:

```
sift = cv2.xfeatures2d.SIFT_create()
rootsift = RootSIFT()
keypoints_all_left_rootsift = []
descriptors_all_left_rootsift = []
points_all_left_rootsift=[]

keypoints_all_right_rootsift = []
descriptors_all_right_rootsift = []
points_all_right_rootsift=[]

for imgs in tqdm(images_left_bgr):
    kpt = sift.detect(imgs,None)
    kpt,descrip = rootsift.compute(imgs, kpt)
    keypoints_all_left_rootsift.append(kpt)
    descriptors_all_left_rootsift.append(descrip)
    points_all_left_rootsift.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
for imgs in tqdm(images_right_bgr):
    kpt = sift.detect(imgs,None)
    kpt,descrip = rootsift.compute(imgs, kpt)
    keypoints_all_right_rootsift.append(kpt)
    descriptors_all_right_rootsift.append(descrip)
    points_all_right_rootsift.append(np.asarray([[p.pt[0], p.pt[1]] for p in kpt]))
```

In [13]:

```
!git clone https://github.com/magicleap/SuperPointPretrainedNetwork.git
```

```
Cloning into 'SuperPointPretrainedNetwork'...
remote: Enumerating objects: 81, done.
remote: Total 81 (delta 0), reused 0 (delta 0), pack-reused 81
Unpacking objects: 100% (81/81), done.
```

In [14]:

```
weights_path = 'SuperPointPretrainedNetwork/superpoint_v1.pth'
cuda = 'False'
```

In [15]:

```
def to_kpts(pts,size=1):
    return [cv2.KeyPoint(pt[0],pt[1],size) for pt in pts]
```

In [16]:

```
torch.cuda.empty_cache()
class SuperPointNet(nn.Module):
    def __init__(self):
        super(SuperPointNet,self).__init__()
        self.relu = nn.ReLU(inplace=True)
        self.pool = nn.MaxPool2d(kernel_size=2, stride=2)
        c1,c2,c3,c4,c5,d1 = 64,64,128,128,256,256
        self.conv1a = nn.Conv2d(1,c1,kernel_size=3,stride=1,padding=1)
        self.conv1b = nn.Conv2d(c1,c1,kernel_size=3,stride=1,padding=1)
        self.conv2a = nn.Conv2d(c1,c2,kernel_size=3,stride=1,padding=1)
        self.conv2b = nn.Conv2d(c2,c2,kernel_size=3,stride=1,padding=1)
        self.conv3a = nn.Conv2d(c2,c3,kernel_size=3,stride=1,padding=1)
        self.conv3b = nn.Conv2d(c3,c3,kernel_size=3,stride=1,padding=1)
        self.conv4a = nn.Conv2d(c3,c4,kernel_size=3,stride=1,padding=1)
        self.conv4b = nn.Conv2d(c4,c4,kernel_size=3,stride=1,padding=1)
        self.convPa = nn.Conv2d(c4,c5,kernel_size=3,stride=1,padding=1)
        self.convPb = nn.Conv2d(c5,65,kernel_size=1,stride=1,padding=0)
        self.convDa = nn.Conv2d(c4,c5,kernel_size=3,stride=1,padding=1)


        self.convDb = nn.Conv2d(c5,d1,kernel_size=1,stride=1,padding=0)
    def forward(self,x):
        x = self.relu(self.conv1a(x))
        x = self.relu(self.conv1b(x))
        x = self.pool(x)
        x = self.relu(self.conv2a(x))
        x = self.relu(self.conv2b(x))
        x = self.pool(x)
        x  = self.relu(self.conv3a(x))
        x = self.relu(self.conv3b(x))
        x = self.pool(x)
        x = self.relu(self.conv4a(x))
        x = self.relu(self.conv4b(x))
        cPa = self.relu(self.convPa(x))
        semi = self.convPb(cPa)
        cDa = self.relu(self.convDa(x))
        desc = self.convDb(cDa)
        dn = torch.norm(desc,p=2,dim=1)
        desc = desc.div(torch.unsqueeze(dn,1))
        return semi,desc


class SuperPointFrontend(object):
    def __init__(self,weights_path,nms_dist,conf_thresh, nn_thresh,cuda=True):
        self.name = 'SuperPoint'
        self.cuda = cuda
        self.nms_dist = nms_dist
        self.conf_thresh = conf_thresh
        self.nn_thresh = nn_thresh
        self.cell = 8
        self.border_remove = 4

        self.net = SuperPointNet()
        if cuda:
            self.net.load_state_dict(torch.load(weights_path))
            self.net = self.net.cuda()
        else:
            self.net.load_state_dict(torch.load(weights_path,map_location=lambda storage
, loc: storage))
        self.net.eval()

    def nms_fast(self,in_corners,H,W,dist_thresh):
        grid = np.zeros((H,W)).astype(int)
        inds = np.zeros((H,W)).astype(int)
        inds1 = np.argsort(-in_corners[2,:])
        corners  = in_corners[:,inds1]
        rcorners = corners[:2,:].round().astype(int)
        if rcorners.shape[1] == 0:
            return np.zeros((3,0)).astype(int), np.zeros(0).astype(int)
        if rcorners.shape[1] == 1:
            out =  np.vstack((rcorners,in_corners[2])).reshape(3,1)
            return out,np.zeros((1)).astype(int)
        for i, rc in enumerate(rcorners.T):
            grid[rcorners[1,i],rcorners[0,i]] =1
            inds[rcorners[1,i],rcorners[0,i]] =i
        pad = dist_thresh
        grid = np.pad(grid,((pad,pad),(pad,pad)),mode='constant')
        count = 0
        for i,rc  in enumerate(rcorners.T):
            pt = (rc[0]+pad, rc[1]+pad)
            if grid[pt[1], pt[0]] == 1:
                grid[pt[1]-pad:pt[1]+pad+1, pt[0]-pad:pt[0]+pad+1]=0


                grid[pt[1], pt[0]] = -1
                count += 1

        keepy, keepx = np.where(grid==-1)
        keepy,keepx = keepy-pad , keepx-pad
        inds_keep = inds[keepy, keepx]
        out  = corners[:,inds_keep]
        values = out[-1,:]
        inds2 = np.argsort(-values)
        out = out[:,inds2]
        out_inds = inds1[inds_keep[inds2]]
        return out, out_inds

    def run(self,img):
        assert img.ndim == 2
        assert img.dtype == np.float32
        H,W = img.shape[0], img.shape[1]
        inp = img.copy()
        inp = (inp.reshape(1,H,W))
        inp = torch.from_numpy(inp)
        inp = torch.autograd.Variable(inp).view(1,1,H,W)
        if self.cuda:
            inp = inp.cuda()
        outs = self.net.forward(inp)
        semi,coarse_desc = outs[0],outs[1]
        semi = semi.data.cpu().numpy().squeeze()


        dense = np.exp(semi)
        dense = dense / (np.sum(dense,axis=0)+.00001)
        nodust = dense[:-1,:,:]
        Hc = int(H / self.cell)
        Wc = int(W  / self.cell)
        nodust = np.transpose(nodust,[1,2,0])
        heatmap = np.reshape(nodust,[Hc,Wc,self.cell,self.cell])
        heatmap = np.transpose(heatmap,[0,2,1,3])
        heatmap = np.reshape(heatmap,[Hc*self.cell, Wc*self.cell])
        prob_map  = heatmap/np.sum(np.sum(heatmap))

        return heatmap,coarse_desc

    def key_pt_sampling(self,img,heat_map,coarse_desc,sampled):
        H,W = img.shape[0], img.shape[1]
        xs,ys = np.where(heat_map >= self.conf_thresh)
        if len(xs) == 0:
            return np.zeros((3,0)),None,None
        print("Number of pts selected:",len(xs))

        pts = np.zeros((3,len(xs)))
        pts[0,:] = ys
        pts[1,:] = xs
        pts[2,:] = heat_map[xs,ys]
        pts,_ = self.nms_fast(pts,H,W,dist_thresh=self.nms_dist)
        inds = np.argsort(pts[2,:])
        pts = pts[:,inds[::-1]]
        bord = self.border_remove
        toremoveW = np.logical_or(pts[0,:] < bord, pts[0,:] >= (W-bord))
        toremoveH = np.logical_or(pts[1,:] < bord, pts[0,:] >= (H-bord))
        toremove = np.logical_or(toremoveW, toremoveH)
        pts = pts[:,~toremove]
        pts = pts[:,0:sampled]
        D = coarse_desc.shape[1]
        if pts.shape[1] == 0:
            desc = np.zeros((D,0))
        else:
            samp_pts = torch.from_numpy(pts[:2,:].copy())
            samp_pts[0,:] = (samp_pts[0,:] / (float(W)/2.))-1.
            samp_pts[1,:] = (samp_pts[1,:] / (float(W)/2.))-1.
            samp_pts = samp_pts.transpose(0,1).contiguous()
            samp_pts = samp_pts.view(1,1,-1,2)
            samp_pts = samp_pts.float()
            if self.cuda:
                samp_pts = samp_pts.cuda()
            desc = nn.functional.grid_sample(coarse_desc, samp_pts)
            desc = desc.data.cpu().numpy().reshape(D,-1)
            desc /= np.linalg.norm(desc,axis=0)[np.newaxis,:]
        return pts,desc
```

In [17]:

```
print('Load pre trained network')
fe = SuperPointFrontend(weights_path = weights_path, nms_dist = 4, conf_thresh  = 0.015,
nn_thresh=0.7,
                        cuda = False)
print('Successfully  loaded pretrained network')
```

```
Load pre trained network
Successfully  loaded pretrained network
```

In [ ]:

```
keypoint_all_left_superpoint = []
descriptor_all_left_superpoint = []
point_all_left_superpoint = []

keypoints_all_right_superpoint = []
descriptors_all_right_superpoint = []
points_all_right_superpoint = []

for ifpth in tqdm(images_left):
    heatmap1, coarse_desc1 = fe.run(ifpth)
    pts_1, desc_1 = fe.key_pt_sampling(ifpth,heatmap1,coarse_desc1,2000)

    keypoint_all_left_superpoint.append(to_kpts(pts_1.T))
    descriptor_all_left_superpoint.append(desc_1.T)
    point_all_left_superpoint.append(pts_1.T)





for rfpth in tqdm(images_right):
    heatmap1, coarse_desc1 = fe.run(rfpth)
    pts_1, desc_1 = fe.key_pt_sampling(rfpth,heatmap1,coarse_desc1,2000)

    keypoints_all_right_superpoint.append(to_kpts(pts_1.T))
    descriptors_all_right_superpoint.append(desc_1.T)
    points_all_right_superpoint.append(pts_1.T)
```

In [ ]:

```
num_kps_superpoint = []
for j in tqdm(keypoint_all_left_superpoint + keypoints_all_right_superpoint):
    num_kps_superpoint.append(len(j))
```

In [ ]:

```
num_kps_brisk = []
for j in tqdm(keypoints_all_left_brisk + keypoints_all_right_brisk):
    num_kps_brisk.append(len(j))
```

In [ ]:

```
num_kps_orb = []
for j  in tqdm(keypoints_all_left_orb + keypoints_all_right_orb):
    num_kps_orb.append(len(j))
```

In [ ]:

```
num_kps_fast = []
for j in tqdm(keypoints_all_left_fast + keypoints_all_right_fast):
    num_kps_fast.append(len(j))
```

In [ ]:

```
num_kps_kaze = []
for j  in tqdm(keypoints_all_left_kaze + keypoints_all_right_kaze):
    num_kps_kaze.append(len(j))
```

In [ ]:

```
num_kps_akaze  = []



for j in tqdm(keypoints_all_left_akaze + keypoints_all_right_akaze):
    num_kps_akaze.append(len(j))
```

In [ ]:

```
num_kps_freak = []
for j in tqdm(keypoints_all_left_freak + keypoints_all_right_freak):
    num_kps_freak.append(len(j))
```

In [18]:

```
num_kps_mser =[]
for j in tqdm(keypoints_all_left_mser + keypoints_all_right_mser):
    num_kps_mser.append(len(j))
```

```
100%|██████████| 101/101 [00:00<00:00, 192294.46it/s]
```

In [ ]:

```
num_kps_gftt =[]
for j in tqdm(keypoints_all_left_gftt + keypoints_all_right_gftt):
    num_kps_gftt.append(len(j))
```

In [ ]:

```
num_kps_daisy = []
for  j in tqdm(keypoints_all_left_daisy + keypoints_all_right_daisy):
    num_kps_daisy.append(j)
```

In [ ]:

```
num_kps_star = []
for  j in tqdm(keypoints_all_left_star + keypoints_all_right_star):
    num_kps_star.append(len(j))
```

In [ ]:

```
num_kps_sift = []
for j in tqdm(keypoints_all_left_sift + keypoints_all_right_sift):
    num_kps_sift.append(len(j))
```

In [ ]:

```
num_kps_surf = []
for j in tqdm(keypoints_all_left_surf + keypoints_all_right_surf):
    num_kps_surf.append(len(j))
```

In [ ]:

```
num_kps_surfsift = []
for j in tqdm(keypoints_all_left_surfsift + keypoints_all_right_surfsift):
    num_kps_surfsift.append(len(j))
```

In [ ]:

```
num_kps_agast  = []
for j in tqdm(keypoints_all_left_agast + keypoints_all_right_agast):
    num_kps_agast.append(len(j))
```

In [19]:

```
def compute_homography_fast(matched_pts1, matched_pts2,thresh=4):
    #matched_pts1 = cv2.KeyPoint_convert(matched_kp1)
    #matched_pts2 = cv2.KeyPoint_convert(matched_kp2)
    # Estimate the homography between the matches using RANSAC
    H, inliers = cv2.findHomography(matched_pts1,matched_pts2,cv2.RANSAC, ransacReprojTh
reshold =thresh)
    inliers = inliers.flatten()
    return H, inliers
```

In [20]:

```
def get_Hmatrix(imgs,keypts,pts,descripts,ratio=0.8,thresh=4,disp=False):
    FLANN_INDEX_KDTREE = 2
    index_params = dict(algorithm=FLANN_INDEX_KDTREE, trees=5)
    search_params = dict(checks=50)
    flann = cv2.FlannBasedMatcher(index_params, search_params)
    #flann = cv2.BFMatcher()
    lff1 = np.float32(descripts[0])
    lff = np.float32(descripts[1])
    matches_lf1_lf = flann.knnMatch(lff1, lff, k=2)
    print("\nNumber of matches",len(matches_lf1_lf))
    matches_4 = []
    ratio = ratio
    # loop over the raw matches
    for m in matches_lf1_lf:
        # ensure the distance is within a certain ratio of each
        # other (i.e. Lowe's ratio test)
        if len(m) == 2 and m[0].distance < m[1].distance * ratio:

            matches_4.append(m[0])
    print("Number of matches After Lowe's Ratio",len(matches_4))
    matches_idx = np.array([m.queryIdx for m in matches_4])
    imm1_pts = np.array([keypts[0][idx].pt for idx in matches_idx])
    matche_idx = np.array([m.trainIdx for m in matches_4])
    imm2_pts = np.array([keypts[1][idx].pt for idx in matche_idx])

    '''
    # Estimate homography 1
    #Compute H1
    # Estimate homography 1
    #Compute H1
    imm1_pts=np.empty((len(matches_4),2))
    imm2_pts=np.empty((len(matches_4),2))
    for i in range(0,len(matches_4)):
    m = matches_4[i]
    (a_x, a_y) = keypts[0][m.queryIdx].pt
    (b_x, b_y) = keypts[1][m.trainIdx].pt
    imm1_pts[i]=(a_x, a_y)
    imm2_pts[i]=(b_x, b_y)
    H=compute_Homography(imm1_pts,imm2_pts)
    #Robustly estimate Homography 1 using RANSAC
    Hn, best_inliers=RANSAC_alg(keypts[0] ,keypts[1], matches_4, nRANSAC=1000, RANSACthre
sh=6)
    '''
    Hn,inliers = compute_homography_fast(imm1_pts,imm2_pts)

    inlier_matchset = np.array(matches_4)[inliers.astype(bool)].tolist()
    print("Number of Robust matches",len(inlier_matchset))
    print("\n")
    '''
    if len(inlier_matchset)<50:
        matches_4 = []
        ratio = 0.80
        # loop over the raw matches
        for m in matches_lf1_lf:
           # ensure the distance is within a certain ratio of each
           # other (i.e. Lowe's ratio test)
           if len(m) == 2 and m[0].distance < m[1].distance * ratio:
           #matches_1.append((m[0].trainIdx, m[0].queryIdx))
           matches_4.append(m[0])
        print("Number of matches After Lowe's Ratio New",len(matches_4))
        matches_idx = np.array([m.queryIdx for m in matches_4])
        imm1_pts = np.array([keypts[0][idx].pt for idx in matches_idx])
        matches_idx = np.array([m.trainIdx for m in matches_4])
        imm2_pts = np.array([keypts[1][idx].pt for idx in matches_idx])
        Hn,inliers = compute_homography_fast_other(imm1_pts,imm2_pts)
        inlier_matchset = np.array(matches_4)[inliers.astype(bool)].tolist()
        print("Number of Robust matches New",len(inlier_matchset))
        print("\n")
        '''
    #H=compute_Homography(imm1_pts,imm2_pts)
    #Robustly estimate Homography 1 using RANSAC
    #Hn=RANSAC_alg(keypts[0] ,keypts[1], matches_4, nRANSAC=1500, RANSACthresh=6)
    #global inlier_matchset
    if disp==True:
        dispimg1=cv2.drawMatches(imgs[0], keypts[0], imgs[1], keypts[1], inlier_matchset
, None,flags=2)
        displayplot(dispimg1,'Robust Matching between Reference Image and Right Image ')
    return Hn/Hn[2,2], len(matches_lf1_lf), len(inlier_matchset)
```

In [21]:

```
from functools import partial
from tqdm import tqdm
tqdm = partial(tqdm, position=0, leave=True)
```

In [ ]:

```
H_left_brisk = []
H_right_brisk = []

num_matches_brisk = []
num_good_matches_brisk = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left
_brisk[j:j+2][::-1],points_all_left_brisk[j:j+2][::-1],descriptors_all_left_brisk[j:j+2]
[::-1])
    H_left_brisk.append(H_a)
    num_matches_brisk.append(matches)
    num_good_matches_brisk.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_rig
ht_brisk[j:j+2][::-1],points_all_right_brisk[j:j+2][::-1],descriptors_all_right_brisk[j:
j+2][::-1])
    H_right_brisk.append(H_a)
    num_matches_brisk.append(matches)
    num_good_matches_brisk.append(gd_matches)
```

In [ ]:

```
H_left_orb = []
H_right_orb = []

num_matches_orb = []
num_good_matches_orb = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left
_orb[j:j+2][::-1],points_all_left_orb[j:j+2][::-1],descriptors_all_left_orb[j:j+2][::-1]
)
    H_left_orb.append(H_a)
    num_matches_orb.append(matches)
    num_good_matches_orb.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_orb[j:j+2][::-1],points_all_right_orb[j:j+2][::-1],descriptors_all_right_orb[j:j+2][::-1])
    H_right_orb.append(H_a)
    num_matches_orb.append(matches)
    num_good_matches_orb.append(gd_matches)
```

In [ ]:

```
H_left_akaze = []
H_right_akaze = []

num_matches_akaze = []
num_good_matches_akaze = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left_akaze[j:j+2][::-1],points_all_left_akaze[j:j+2][::-1],descriptors_all_left_akaze[j:j+2][::-1])
    H_left_akaze.append(H_a)
    num_matches_akaze.append(matches)
    num_good_matches_akaze.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_akaze[j:j+2][::-1],points_all_right_akaze[j:j+2][::-1],descriptors_all_right_akaze[j:j+2][::-1])
    H_right_akaze.append(H_a)
    num_matches_akaze.append(matches)
    num_good_matches_akaze.append(gd_matches)
```

In [ ]:

```
H_left_kaze = []
H_right_kaze = []

num_matches_kaze = []
num_good_matches_kaze = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left_kaze[j:j+2][::-1],points_all_left_kaze[j:j+2][::-1],descriptors_all_left_kaze[j:j+2][::-1])
    H_left_kaze.append(H_a)
    num_matches_kaze.append(matches)
    num_good_matches_kaze.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_kaze[j:j+2][::-1],points_all_right_kaze[j:j+2][::-1],descriptors_all_right_kaze[j:j+2][::-1])
    H_right_kaze.append(H_a)
    num_matches_kaze.append(matches)
    num_good_matches_kaze.append(gd_matches)
```

In [ ]:

```
H_left_freak = []
H_right_freak = []

num_matches_freak = []
num_good_matches_freak = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left_freak[j:j+2][::-1],points_all_left_freak[j:j+2][::-1],descriptors_all_left_freak[j:j+2][::-1])
    H_left_freak.append(H_a)
    num_matches_freak.append(matches)
    num_good_matches_freak.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_freak[j:j+2][::-1],points_all_right_freak[j:j+2][::-1],descriptors_all_right_freak[j:j+2][::-1])
    H_right_freak.append(H_a)
    num_matches_freak.append(matches)
    num_good_matches_freak.append(gd_matches)
```

In [23]:

```
H_left_mser = []
H_right_mser = []

num_matches_mser = []
num_good_matches_mser = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left_mser[j:j+2][::-1],points_all_left_mser[j:j+2][::-1],descriptors_all_left_mser[j:j+2][::-1])
    H_left_mser.append(H_a)
    num_matches_mser.append(matches)
    num_good_matches_mser.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_mser[j:j+2][::-1],points_all_right_mser[j:j+2][::-1],descriptors_all_right_mser[j:j+2][::-1])
    H_right_mser.append(H_a)
    num_matches_mser.append(matches)
    num_good_matches_mser.append(gd_matches)
```

```
  3%|▌         | 2/61 [00:00<00:10,  5.82it/s]
```

```
Number of matches 1714
Number of matches After Lowe's Ratio 176
Number of Robust matches 49



Number of matches 1962
Number of matches After Lowe's Ratio 120
Number of Robust matches 39
```

```
  7%|▋         | 4/61 [00:00<00:09,  5.94it/s]
```

```
Number of matches 1751
Number of matches After Lowe's Ratio 11
Number of Robust matches 4



Number of matches 1794
Number of matches After Lowe's Ratio 411
Number of Robust matches 159
```

```
  8%|▊         | 5/61 [00:00<00:09,  5.86it/s]
```

```
Number of matches 1883
Number of matches After Lowe's Ratio 80
Number of Robust matches 26
```

```
 11%|█         | 7/61 [00:01<00:09,  5.49it/s]
```

```
Number of matches 1658
Number of matches After Lowe's Ratio 201
Number of Robust matches 71



Number of matches 1770
Number of matches After Lowe's Ratio 96
Number of Robust matches 34
```

```
 15%|█▍        | 9/61 [00:01<00:08,  6.12it/s]
```

```
Number of matches 1423
Number of matches After Lowe's Ratio 203
Number of Robust matches 72



Number of matches 1746
Number of matches After Lowe's Ratio 189
Number of Robust matches 76
```

```
 16%|█▋        | 10/61 [00:01<00:08,  6.31it/s]
```

```
Number of matches 1024
Number of matches After Lowe's Ratio 85
Number of Robust matches 39



Number of matches 1338
Number of matches After Lowe's Ratio 272
Number of Robust matches 144
```

```
 20%|█▉        | 12/61 [00:01<00:06,  7.55it/s]
```

```
Number of matches 1120
Number of matches After Lowe's Ratio 49
Number of Robust matches 24



Number of matches 1366
Number of matches After Lowe's Ratio 141
Number of Robust matches 69
```

```
 25%|███        | 15/61 [00:02<00:05,  8.33it/s]
```

```
Number of matches 1280
Number of matches After Lowe's Ratio 223
Number of Robust matches 134


Number of matches 1346
Number of matches After Lowe's Ratio 287
Number of Robust matches 165
```

```
 28%|███        | 17/61 [00:02<00:05,  7.37it/s]
```

```
Number of matches 1443
Number of matches After Lowe's Ratio 280
Number of Robust matches 167


Number of matches 1670
Number of matches After Lowe's Ratio 346
Number of Robust matches 182
```

```
 31%|████       | 19/61 [00:02<00:06,  6.62it/s]
```

```
Number of matches 1624
Number of matches After Lowe's Ratio 537
Number of Robust matches 258


Number of matches 1719
Number of matches After Lowe's Ratio 544
Number of Robust matches 319
```

```
 34%|████       | 21/61 [00:03<00:06,  6.08it/s]
```

```
Number of matches 1830
Number of matches After Lowe's Ratio 394
Number of Robust matches 272


Number of matches 1807
Number of matches After Lowe's Ratio 224
Number of Robust matches 99
```

```
 38%|████       | 23/61 [00:03<00:06,  6.00it/s]
```

```
Number of matches 1708
Number of matches After Lowe's Ratio 463
Number of Robust matches 212


Number of matches 1744
Number of matches After Lowe's Ratio 227
Number of Robust matches 94
```

```
 41%|████      | 25/61 [00:03<00:05,  6.17it/s]
```

```
Number of matches 1672
Number of matches After Lowe's Ratio 403
Number of Robust matches 161



Number of matches 1673
Number of matches After Lowe's Ratio 8
Number of Robust matches 5
```

```
 44%|████▍     | 27/61 [00:04<00:05,  6.45it/s]
```

```
Number of matches 1484
Number of matches After Lowe's Ratio 38
Number of Robust matches 15



Number of matches 1694
Number of matches After Lowe's Ratio 342
Number of Robust matches 126
```

```
 48%|████▊     | 29/61 [00:04<00:05,  5.91it/s]
```

```
Number of matches 1933
Number of matches After Lowe's Ratio 45
Number of Robust matches 20



Number of matches 2169
Number of matches After Lowe's Ratio 39
Number of Robust matches 15
```

```
 49%|████▉     | 30/61 [00:04<00:05,  5.62it/s]
```

```
Number of matches 2232
Number of matches After Lowe's Ratio 329
Number of Robust matches 146
```

```
 51%|█████     | 31/61 [00:04<00:05,  5.17it/s]
```

```
Number of matches 2363
Number of matches After Lowe's Ratio 226
Number of Robust matches 76
```

```
 54%|█████▍    | 33/61 [00:05<00:05,  5.12it/s]
```

```
Number of matches 1904
Number of matches After Lowe's Ratio 9
Number of Robust matches 5



Number of matches 1802
Number of matches After Lowe's Ratio 317
Number of Robust matches 118
```

```
 57%|█████▋    | 35/61 [00:05<00:04,  5.42it/s]
```

```
Number of matches 1782
Number of matches After Lowe's Ratio 408
Number of Robust matches 164



Number of matches 2017
Number of matches After Lowe's Ratio 351
Number of Robust matches 147


 59%|█████▉    | 36/61 [00:05<00:04,  5.24it/s]

Number of matches 2392
Number of matches After Lowe's Ratio 391
Number of Robust matches 135


 61%|██████    | 37/61 [00:06<00:04,  4.88it/s]

Number of matches 2528
Number of matches After Lowe's Ratio 386
Number of Robust matches 147


 62%|██████▏   | 38/61 [00:06<00:05,  4.51it/s]

Number of matches 2886
Number of matches After Lowe's Ratio 620
Number of Robust matches 254


 64%|██████▍   | 39/61 [00:06<00:05,  4.20it/s]

Number of matches 2399
Number of matches After Lowe's Ratio 550
Number of Robust matches 224


 66%|██████▌   | 40/61 [00:06<00:05,  4.19it/s]

Number of matches 2045
Number of matches After Lowe's Ratio 555
Number of Robust matches 270



Number of matches 1840
Number of matches After Lowe's Ratio 509
 69%|██████▉   | 42/61 [00:07<00:03,  4.82it/s]

Number of Robust matches 257



Number of matches 1576
Number of matches After Lowe's Ratio 425
Number of Robust matches 230


 72%|███████▏  | 44/61 [00:07<00:03,  5.41it/s]

Number of matches 1563
Number of matches After Lowe's Ratio 474
Number of Robust matches 255



Number of matches 1735
Number of matches 1753
Number of matches After Lowe's Ratio 443
Number of Robust matches 237


 75%|███████▌  | 46/61 [00:07<00:02,  5.72it/s]

Number of matches 1748
Number of matches After Lowe's Ratio 514
Number of Robust matches 225



Number of matches 1671
Number of matches After Lowe's Ratio 540
Number of Robust matches 267


 79%|███████▊  | 48/61 [00:08<00:02,  6.40it/s]

Number of matches 1437
Number of matches After Lowe's Ratio 409
Number of Robust matches 186



Number of matches 1164
Number of matches After Lowe's Ratio 178
Number of Robust matches 106


 82%|████████▏ | 50/61 [00:08<00:01,  7.55it/s]

Number of matches 1251
Number of matches After Lowe's Ratio 364
Number of Robust matches 192



Number of matches 1223
Number of matches After Lowe's Ratio 313
Number of Robust matches 167


 84%|████████▎ | 51/61 [00:08<00:01,  7.86it/s]

Number of matches 1152
Number of matches After Lowe's Ratio 245
Number of Robust matches 130



Number of matches 1304
Number of matches After Lowe's Ratio 261
Number of Robust matches 165


 89%|████████▊ | 54/61 [00:08<00:00,  8.51it/s]

Number of matches 1393
Number of matches After Lowe's Ratio 377
Number of Robust matches 222



Number of matches 1378
Number of matches After Lowe's Ratio 207
Number of Robust matches 109
```

```
 92%|█████████▏| 56/61 [00:09<00:00,  7.79it/s]
```

```
Number of matches 1539
Number of matches After Lowe's Ratio 193
Number of Robust matches 100



Number of matches 1645
Number of matches After Lowe's Ratio 286
Number of Robust matches 118
```

```
 95%|█████████▌| 58/61 [00:09<00:00,  6.77it/s]
```

```
Number of matches 1731
Number of matches After Lowe's Ratio 381
Number of Robust matches 144



Number of matches 1719
Number of matches After Lowe's Ratio 248
Number of Robust matches 104
```

```
 98%|█████████▊| 60/61 [00:09<00:00,  6.10it/s]
  0%|          | 0/40 [00:00<?, ?it/s]
```

```
Number of matches 1716
Number of matches After Lowe's Ratio 438
Number of Robust matches 179



Number of matches 1450
Number of matches After Lowe's Ratio 70
Number of Robust matches 34
```

```
  5%|▌         | 2/40 [00:00<00:06,  6.32it/s]
```

```
Number of matches 1727
Number of matches After Lowe's Ratio 167
Number of Robust matches 62



Number of matches 1837
Number of matches After Lowe's Ratio 283
Number of Robust matches 148
```

```
 10%|█         | 4/40 [00:00<00:05,  7.00it/s]
```

```
Number of matches 1372
Number of matches After Lowe's Ratio 338
Number of Robust matches 167



Number of matches 940
Number of matches After Lowe's Ratio 136
Number of Robust matches 85
```

```
 15%|█▌        | 6/40 [00:00<00:04,  7.87it/s]
```

```
Number of matches 1483
Number of matches After Lowe's Ratio 81
Number of Robust matches 46



Number of matches 1174
Number of matches After Lowe's Ratio 285
Number of Robust matches 174


 20%|██        | 8/40 [00:01<00:04,  7.78it/s]

Number of matches 1550
Number of matches After Lowe's Ratio 210
Number of Robust matches 116



Number of matches 1607
Number of matches After Lowe's Ratio 537
Number of Robust matches 328


 25%|██▌       | 10/40 [00:01<00:04,  6.72it/s]

Number of matches 1545
Number of matches After Lowe's Ratio 508
Number of Robust matches 326



Number of matches 1864
Number of matches After Lowe's Ratio 523
Number of Robust matches 281


 30%|███       | 12/40 [00:01<00:04,  5.90it/s]

Number of matches 1881
Number of matches After Lowe's Ratio 594
Number of Robust matches 379



Number of matches 2160
Number of matches After Lowe's Ratio 354
Number of Robust matches 222


 32%|███▎      | 13/40 [00:01<00:04,  5.64it/s]

Number of matches 2129
Number of matches After Lowe's Ratio 520
Number of Robust matches 295


 35%|███▌      | 14/40 [00:02<00:05,  5.05it/s]

Number of matches 2188
Number of matches After Lowe's Ratio 486
Number of Robust matches 244


 38%|███▊      | 15/40 [00:02<00:05,  4.94it/s]

Number of matches 2205
Number of matches After Lowe's Ratio 486
Number of Robust matches 220
Number of Robust matches 220
```

```
 40%|████      | 16/40 [00:02<00:04,  4.87it/s]
```

```
Number of matches 2087
Number of matches After Lowe's Ratio 388
Number of Robust matches 168
```

```
 45%|████▌     | 18/40 [00:03<00:04,  5.02it/s]
```

```
Number of matches 2027
Number of matches After Lowe's Ratio 607
Number of Robust matches 252


Number of matches 1893
Number of matches After Lowe's Ratio 463
Number of Robust matches 185
```

```
 48%|████▊     | 19/40 [00:03<00:04,  5.09it/s]
```

```
Number of matches 2015
Number of matches After Lowe's Ratio 564
Number of Robust matches 196
```

```
 50%|█████     | 20/40 [00:03<00:04,  4.87it/s]
```

```
Number of matches 2084
Number of matches After Lowe's Ratio 546
Number of Robust matches 167


Number of matches 2180
Number of matches After Lowe's Ratio 301
```

```
 55%|█████▌    | 22/40 [00:03<00:03,  5.07it/s]
```

```
Number of Robust matches 125


Number of matches 1926
Number of matches After Lowe's Ratio 278
Number of Robust matches 99
```

```
 57%|█████▋    | 23/40 [00:04<00:03,  4.82it/s]
```

```
Number of matches 2672
Number of matches After Lowe's Ratio 114
Number of Robust matches 37
```

```
 60%|██████    | 24/40 [00:04<00:03,  4.57it/s]
```

```
Number of matches 2489
Number of matches After Lowe's Ratio 441
Number of Robust matches 146
```

```
 62%|██████▎   | 25/40 [00:04<00:03,  4.56it/s]
```

```
Number of matches 2596
Number of matches 2390
Number of matches After Lowe's Ratio 4
Number of Robust matches 4
```

```
 65%|██████▌   | 26/40 [00:04<00:03,  4.54it/s]
```

```
Number of matches 2358
Number of matches After Lowe's Ratio 270
Number of Robust matches 106
```

```
 68%|██████▊   | 27/40 [00:04<00:02,  4.55it/s]
```

```
Number of matches 2283
Number of matches After Lowe's Ratio 341
Number of Robust matches 122
```

```
 72%|███████▎  | 29/40 [00:05<00:02,  4.79it/s]
```

```
Number of matches 1969
Number of matches After Lowe's Ratio 474
Number of Robust matches 190


Number of matches 2112
Number of matches After Lowe's Ratio 282
Number of Robust matches 124
```

```
 75%|███████▌  | 30/40 [00:05<00:02,  4.86it/s]
```

```
Number of matches 2034
Number of matches After Lowe's Ratio 301
Number of Robust matches 100
```

```
 78%|███████▊  | 31/40 [00:05<00:01,  4.90it/s]
```

```
Number of matches 1977
Number of matches After Lowe's Ratio 367
Number of Robust matches 143


Number of matches 1938
Number of matches After Lowe's Ratio 586
```

```
 82%|████████▎ | 33/40 [00:06<00:01,  4.99it/s]
```

```
Number of Robust matches 238


Number of matches 2002
Number of matches After Lowe's Ratio 368
Number of Robust matches 130
```

```
 85%|████████▌ | 34/40 [00:06<00:01,  5.05it/s]
```

```
Number of matches 1938
Number of matches After Lowe's Ratio 63
Number of Robust matches 23
```

```
 90%|█████████ | 36/40 [00:06<00:00,  5.07it/s]
 90%|█████████ | 36/40 [00:06<00:00,  5.07it/s]
```

```
Number of matches 1964
Number of matches After Lowe's Ratio 362
Number of Robust matches 174



Number of matches 2027
Number of matches After Lowe's Ratio 273
Number of Robust matches 109
```

```
 95%|█████████▌| 38/40 [00:07<00:00,  5.14it/s]
```

```
Number of matches 2004
Number of matches After Lowe's Ratio 161
Number of Robust matches 87



Number of matches 2045
Number of matches After Lowe's Ratio 290
Number of Robust matches 166
```

```
 98%|█████████▊| 39/40 [00:07<00:00,  5.31it/s]
```

```
Number of matches 1695
Number of matches After Lowe's Ratio 291
Number of Robust matches 140
```

In [ ]:

```
H_left_superpoint = []
H_right_superpoint = []

num_matches_superpoint = []
num_good_matches_superpoint = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoint_all_left_superpoint[j:j+2][::-1],point_all_left_superpoint[j:j+2][::-1],descriptor_all_left_superpoint[j:j+2][::-1])
    H_left_superpoint.append(H_a)
    num_matches_superpoint.append(matches)
    num_good_matches_superpoint.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_superpoint[j:j+2][::-1],points_all_right_superpoint[j:j+2][::-1],descriptors_all_right_superpoint[j:j+2][::-1])
    H_right_superpoint.append(H_a)
    num_matches_superpoint.append(matches)
    num_good_matches_superpoint.append(gd_matches)
```

In [ ]:

```
H_left_gftt = []
H_right_gftt = []

num_matches_gftt = []
```

```
num_good_matches_gftt = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left
_gftt[j:j+2][::-1],points_all_left_gftt[j:j+2][::-1],descriptors_all_left_gftt[j:j+2][::
-1])
    H_left_gftt.append(H_a)
    num_matches_gftt.append(matches)
    num_good_matches_gftt.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_rig
ht_gftt[j:j+2][::-1],points_all_right_gftt[j:j+2][::-1],descriptors_all_right_gftt[j:j+2
][::-1])
    H_right_gftt.append(H_a)
    num_matches_gftt.append(matches)
    num_good_matches_gftt.append(gd_matches)
```

In [ ]:

```
H_left_daisy = []
H_right_daisy = []

num_matches_daisy = []
num_good_matches_daisy = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left
_daisy[j:j+2][::-1],points_all_left_daisy[j:j+2][::-1],descriptors_all_left_daisy[j:j+2]
[::-1])
    H_left_daisy.append(H_a)
    num_matches_daisy.append(matches)
    num_good_matches_daisy.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_rig
ht_daisy[j:j+2][::-1],points_all_right_daisy[j:j+2][::-1],descriptors_all_right_daisy[j:
j+2][::-1])
    H_right_daisy.append(H_a)
    num_matches_daisy.append(matches)
    num_good_matches_daisy.append(gd_matches)
```

In [ ]:

```
H_left_fast = []
H_right_fast = []

num_matches_fast = []
num_good_matches_fast = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left
_fast[j:j+2][::-1],points_all_left_fast[j:j+2][::-1],descriptors_all_left_fast[j:j+2][::
-1])
    H_left_fast.append(H_a)
    num_matches_fast.append(matches)
    num_good_matches_fast.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_fast[j:j+2][::-1],points_all_right_fast[j:j+2][::-1],descriptors_all_right_fast[j:j+2][::-1])
    H_right_fast.append(H_a)
    num_matches_fast.append(matches)
    num_good_matches_fast.append(gd_matches)
```

In [ ]:

```
H_left_star = []
H_right_star = []

num_matches_star = []
num_good_matches_star = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left_star[j:j+2][::-1],points_all_left_star[j:j+2][::-1],descriptors_all_left_brief[j:j+2][::-1])
    H_left_star.append(H_a)
    num_matches_star.append(matches)
    num_good_matches_star.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_star[j:j+2][::-1],points_all_right_star[j:j+2][::-1],descriptors_all_right_brief[j:j+2][::-1])
    H_right_star.append(H_a)
    num_matches_star.append(matches)
    num_good_matches_star.append(gd_matches)
```

In [ ]:

```
H_left_sift = []
H_right_sift = []

num_matches_sift = []
num_good_matches_sift = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left_sift[j:j+2][::-1],points_all_left_sift[j:j+2][::-1],descriptors_all_left_sift[j:j+2][::-1])
    H_left_sift.append(H_a)
    num_matches_sift.append(matches)
    num_good_matches_sift.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_sift[j:j+2][::-1],points_all_right_sift[j:j+2][::-1],descriptors_all_right_sift[j:j+2][::-1])
    H_right_sift.append(H_a)
    num_matches_sift.append(matches)
    num_good_matches_sift.append(gd_matches)
```

In [ ]:

```
H_left_surf = []
H_right_surf = []

num_matches_surf = []
num_good_matches_surf = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left_surf[j:j+2][::-1],points_all_left_surf[j:j++2][::-1],descriptors_all_left_surf[j:j+2][::-1])
    H_left_surf.append(H_a)
    num_matches_surf.append(matches)
    num_good_matches_surf.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_surf[j:j+2][::-1],points_all_right_surf[j:j+2][::-1],descriptors_all_right_surf[j:j+2][::-1])
    H_right_surf.append(H_a)
    num_matches_surf.append(matches)
    num_good_matches_surf.append(gd_matches)
```

In [ ]:

```
H_left_surfsift = []
H_right_surfsift = []

num_matches_surfsift = []
num_good_matches_surfsift = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left_surfsift[j:j+2][::-1],points_all_left_surfsift[j:j++2][::-1],descriptors_all_left_surfsift[j:j+2][::-1])
    H_left_surfsift.append(H_a)
    num_matches_surfsift.append(matches)
    num_good_matches_surfsift.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_right_surfsift[j:j+2][::-1],points_all_right_surfsift[j:j+2][::-1],descriptors_all_right_surfsift[j:j+2][::-1])
    H_right_surfsift.append(H_a)
    num_matches_surfsift.append(matches)
    num_good_matches_surfsift.append(gd_matches)
```

In [ ]:

```
H_left_agast = []
H_right_agast = []

num_matches_agast = []
num_good_matches_agast = []

for j in tqdm(range(len(images_left))):
    if j==len(images_left)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_left_bgr[j:j+2][::-1],keypoints_all_left
_agast[j:j+2][::-1],points_all_left_agast[j:j+2][::-1],descriptors_all_left_agast[j:j+2]
[::-1])
    H_left_agast.append(H_a)
    num_matches_agast.append(matches)
    num_good_matches_agast.append(gd_matches)

for j in tqdm(range(len(images_right))):
    if j==len(images_right)-1:
        break

    H_a,matches,gd_matches = get_Hmatrix(images_right_bgr[j:j+2][::-1],keypoints_all_rig
ht_agast[j:j+2][::-1],points_all_right_agast[j:j+2][::-1],descriptors_all_right_agast[j:
j+2][::-1])
    H_right_agast.append(H_a)
    num_matches_agast.append(matches)
    num_good_matches_agast.append(gd_matches)
```

In [24]:

```
def warpnImages(images_left, images_right,H_left,H_right):
    #img1-centre,img2-left,img3-right

    h, w = images_left[0].shape[:2]

    pts_left = []
    pts_right = []

    pts_centre = np.float32([[0, 0], [0, h], [w, h], [w, 0]]).reshape(-1, 1, 2)

    for j in range(len(H_left)):
      pts = np.float32([[0, 0], [0, h], [w, h], [w, 0]]).reshape(-1, 1, 2)
      pts_left.append(pts)

    for j in range(len(H_right)):
      pts = np.float32([[0, 0], [0, h], [w, h], [w, 0]]).reshape(-1, 1, 2)
      pts_right.append(pts)

    pts_left_transformed=[]
    pts_right_transformed=[]

    for j,pts in enumerate(pts_left):
      if j==0:
        H_trans = H_left[j]
      else:
        H_trans = H_trans@H_left[j]
      pts_ = cv2.perspectiveTransform(pts, H_trans)
      pts_left_transformed.append(pts_)

    for j,pts in enumerate(pts_right):
      if j==0:
        H_trans = H_right[j]
      else:
        H_trans = H_trans@H_right[j]
      pts_ = cv2.perspectiveTransform(pts, H_trans)
      pts_right_transformed.append(pts_)


    print('Step1:Done')


    #pts = np.concatenate((pts1, pts2_), axis=0)

    pts_concat = np.concatenate((pts_centre,np.concatenate(np.array(pts_left_transformed
),axis=0),np.concatenate(np.array(pts_right_transformed),axis=0)), axis=0)

    [xmin, ymin] = np.int32(pts_concat.min(axis=0).ravel() - 0.5)
    [xmax, ymax] = np.int32(pts_concat.max(axis=0).ravel() + 0.5)
    t = [-xmin, -ymin]
    Ht = np.array([[1, 0, t[0]], [0, 1, t[1]], [0, 0, 1]])  # translate

    print('Step2:Done')


    return xmax,xmin,ymax,ymin,t,h,w,Ht
```

In [25]:

```
def final_steps_left_union(images_left,H_left,xmax,xmin,ymax,ymin,t,h,w,Ht):
    for j,H in enumerate(H_left):
        if j==  0:
            H_trans = Ht@H

        else:
            H_trans = H_trans@H
        result =  cv2.warpPerspective(images_left[j+1],H_trans,(xmax-xmin,ymax-ymin))
        warp_img_init_curr = result

        if j == 0:
            result[t[1]:h+t[1],t[0]:w+t[0]] = images_left[0]
            warp_img_init_prev = result
            continue
        black_pixels = np.where((warp_img_init_prev[:,:,0]==0)&(warp_img_init_prev[:,:,1
]==0)&(warp_img_init_prev[:,:,2]==0))
        warp_img_init_prev[black_pixels] = warp_img_init_curr[black_pixels]

    print('step31:Done')
    return warp_img_init_prev

def final_step_right_union(warp_img_prev,images_right,H_right,xmax,xmin,ymax,ymin,t,h,w,
Ht):
    for j,H in enumerate(H_right):
        if j==  0:
            H_trans = Ht@H
        else:
            H_trans = H_trans@H
        result =  cv2.warpPerspective(images_right[j+1],H_trans,(xmax-xmin,ymax-ymin))
        warp_img_init_curr = result



        black_pixels = np.where((warp_img_prev[:,:,0]==0)&(warp_img_prev[:,:,1]==0)&(war
p_img_prev[:,:,2]==0))
        warp_img_prev[black_pixels] = warp_img_init_curr[black_pixels]

    print('step32:Done')
    return warp_img_prev
```

In [26]:

```
xmax,xmin,ymax,ymin,t,h,w,Ht = warpnImages(images_left_bgr, images_right_bgr,H_left_mser
,H_right_mser)
```

```
Step1:Done
Step2:Done
```

In [27]:

```
warp_imgs_left = final_steps_left_union(images_left_bgr,H_left_mser,xmax,xmin,ymax,ymin,t
,h,w,Ht)
```

```
step31:Done
```

In [29]:

```
warp_imgs_all_freak = final_step_right_union(warp_imgs_left,images_right_bgr,H_right_mser
,xmax,xmin,ymax,ymin,t,h,w,Ht)
```

```
step32:Done
```

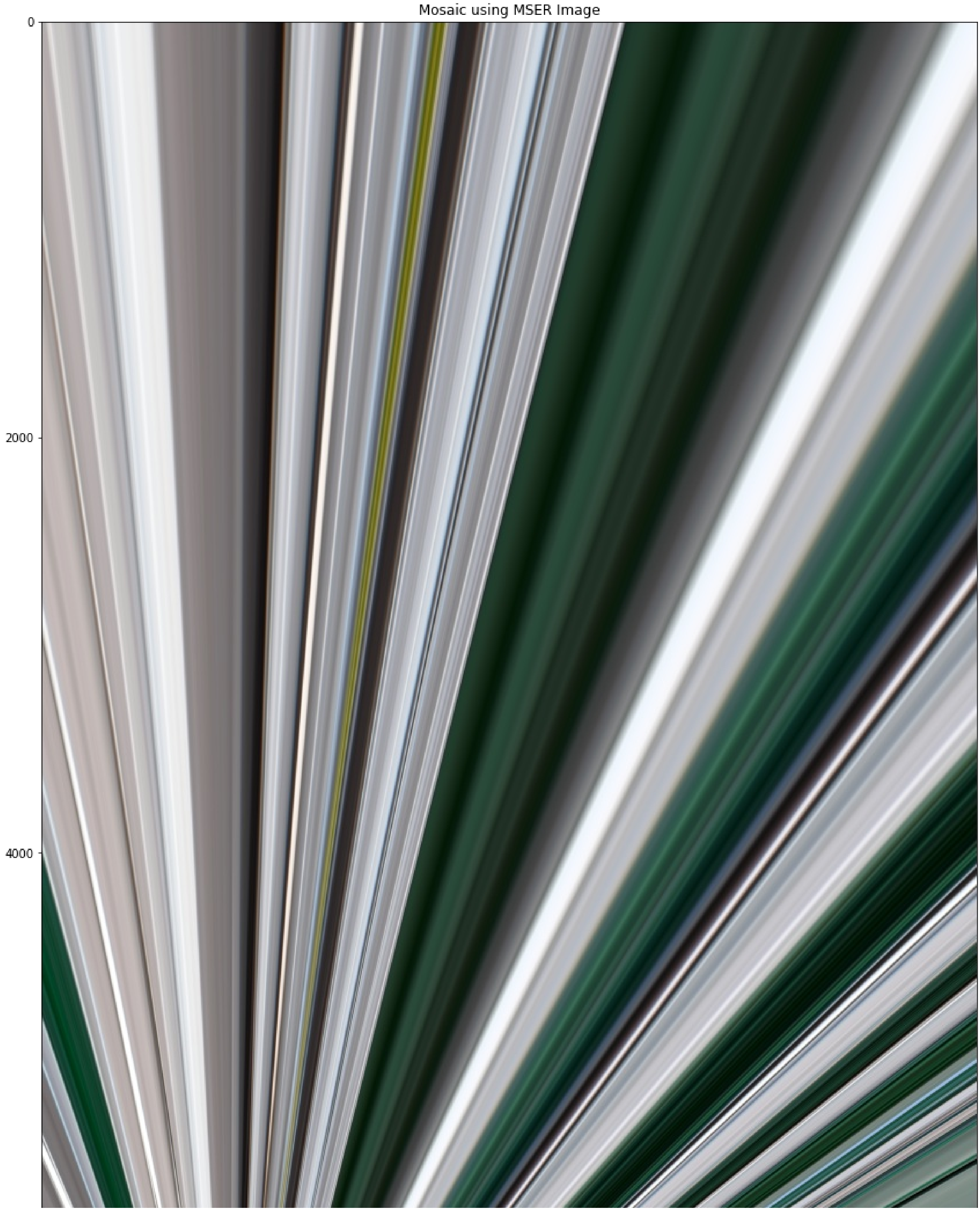
With parameters as delta = 5, min_area = 70 ,area_threshold = 2.01

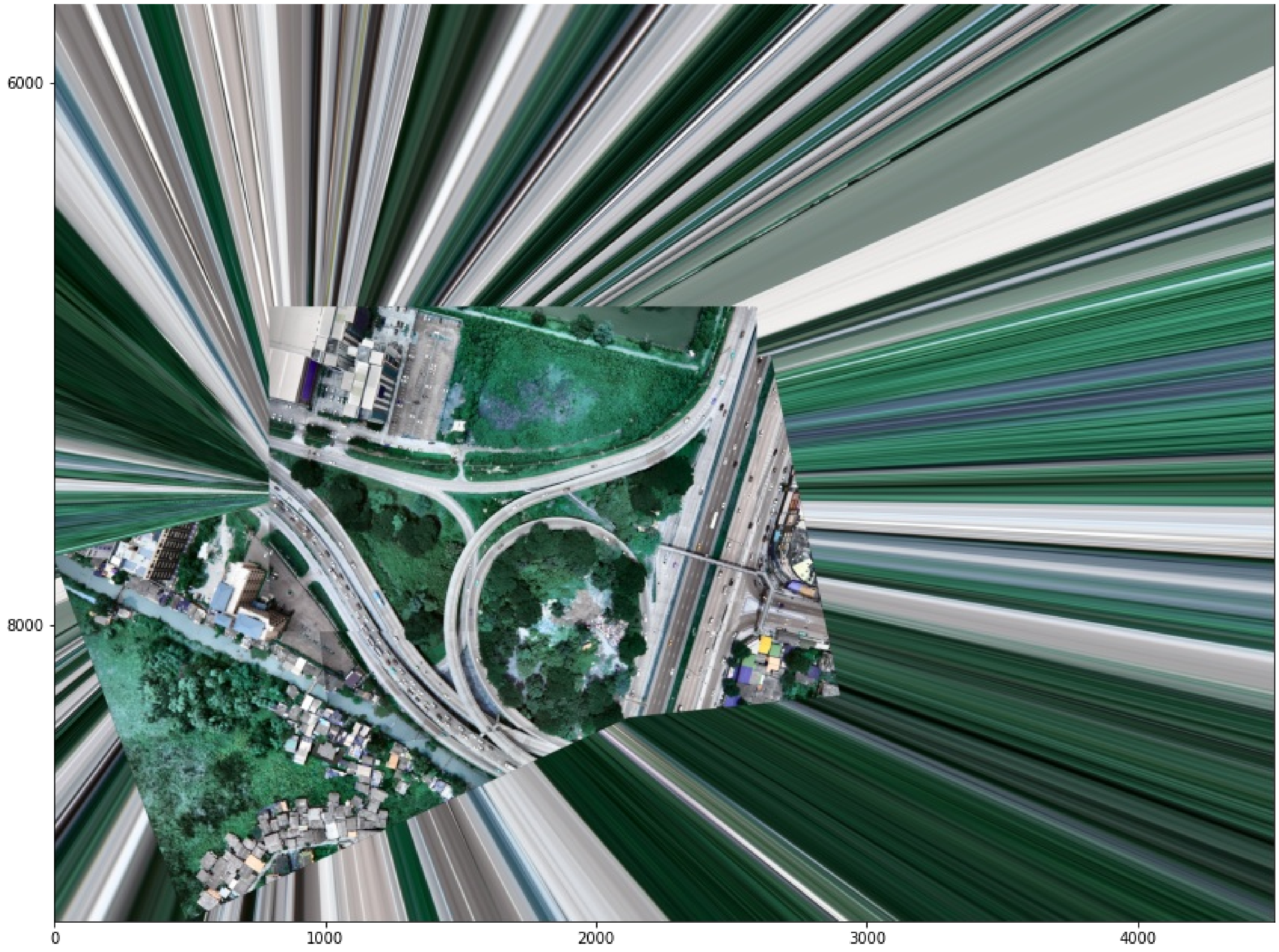
In [30]:

```
plt.figure(figsize=(20,30))
plt.imshow(warp_imgs_all_freak)
plt.title('Mosaic using MSER Image')
```

Out[30]:

```
Text(0.5, 1.0, 'Mosaic using MSER Image')
```





In [ ]:

```
xmax,xmin,ymax,ymin,t,h,w,Ht =warpnImages(images_left_bgr, images_right_bgr,H_left_agast
,H_right_agast)
```

In [ ]:

```
warp_imgs_left = final_steps_left_union(images_left_bgr,H_left_agast,xmax,xmin,ymax,ymin,
t,h,w,Ht)
```

In [ ]:

```
warp_imgs_all_agast = final_step_right_union(warp_imgs_left,images_right_bgr,H_right_agas
t,xmax,xmin,ymax,ymin,t,h,w,Ht)
```

In [ ]:

```
plt.figure(figsize=(20,20))

plt.imshow(warp_imgs_all_agast)
plt.title(' Mosaic using AGAST Image')
```

In [ ]:

```
omax,omin,umax,umin,T,H,W,HT = warpnImages(images_left_bgr, images_right_bgr,H_left_dais
y,H_right_daisy)
```

In [ ]:

```
warp_img = final_steps_left_union(images_left_bgr,H_left_daisy,omax,omin,umax,umin,T,H,W
,HT)
```

In [ ]:

```
warp_imgs_all_orb = final_step_right_union(warp_img,images_right_bgr,H_right_daisy,omax,o
min,umax,umin,T,H,W,HT)
```

In [ ]:

```
omax,omin,umax,umin,T,H,W,HT = warpnImages(images_left_bgr_no_enhance, images_right_bgr_no_enhance,H_left_daisy,H_right_daisy)
```

In [ ]:

```
warp_img = final_steps_left_union(images_left_bgr_no_enhance,H_left_daisy,omax,omin,umax,umin,T,H,W,HT)
```

In [ ]:

```
warp_imgs_all_daisy = final_step_right_union(warp_img,images_right_bgr_no_enhance,H_right_daisy,omax,omin,umax,umin,T,H,W,HT)
```

In [ ]:

```
plt.figure(figsize=(20,20))
plt.imshow(warp_imgs_all_daisy)
plt.title(' Mosaic using DAISY Image')
```

In [ ]:

```
mmax,mmin,nmax,nmin,d,e,f,g = warpnImages(images_left_bgr_no_enhance, images_right_bgr_no_enhance,H_left_fast,H_right_fast)
```

In [ ]:

```
warp_imgs_fast = final_steps_left_union(images_left_bgr_no_enhance,H_left_fast,mmax,mmin,nmax,nmin,d,e,f,g)
```

In [ ]:

```
warp_imgs_all_fast = final_step_right_union(images_right_bgr_no_enhnace,H_right_fast,mmax,mmin,nmax,nmin,d,e,f,g)
```

With threshold 10 , & binary compression = True

In [ ]:

```
plt.figure(figsize=(20,20))
plt.imshow(warp_imgs_all_fast)
plt.title(' Mosaic using FAST Image')
```

In [ ]:

```
omax,omin,umax,umin,T,H,W,HT = warpnImages(images_left_bgr_no_enhance, images_right_bgr_no_enhance,H_left_fast,H_right_fast)
```

In [ ]:

```
warp_img = final_steps_left_union(images_left_bgr_no_enhance,H_left_fast,omax,omin,umax,umin,T,H,W,HT)
```

In [ ]:

```
warp_imgs_all_fast = final_step_right_union(warp_img,images_right_bgr_no_enhance,H_right_fast,omax,omin,umax,umin,T,H,W,HT)
```

With threshold 5 & binary Compression False

In [ ]:

```
plt.figure(figsize=(20,20))
plt.imshow(warp_imgs_all_fast)
plt.title('Mosaic using Fast Image')
```

In [ ]:

```
mmax,mmin,nmax,nmin,d,e,f,g = warpnImages(images_left_bgr_no_enhance, images_right_bgr_no_enhance,H_left_fast,H_right_fast)
```

In [ ]:

```
warp_imgs_fast = final_steps_left_union(images_left_bgr_no_enhance,H_left_fast,mmax,mmin,nmax,nmin,d,e,f,g)
```

In [ ]:

```
warp_imgs_all_fast = final_step_right_union(images_right_bgr_no_enhnace,H_right_fast,mmax,mmin,nmax,nmin,d,e,f,g)
```

With threshold 3 & binary Compression False

With threshold 3 & binary compression even feature extraction stopped and ram crashed

In [ ]:

```
omax,omin,umax,umin,T,H,W,HT = warpnImages(images_left_bgr_no_enhance, images_right_bgr_no_enhance,H_left_gftt,H_right_gftt)
```

In [ ]:

```
warp_img_gftt = final_steps_left_union(images_left_bgr_no_enhance,H_left_gftt,omax,omin,umax,umin,T,H,W,HT)
```

In [ ]:

```
warp_imgs_all_gftt = final_step_right_union(warp_img_gftt,images_right_bgr_no_enhance,H_right_gftt,omax,omin,umax,umin,T,H,W,HT)
```

qualityLevel = 0.07,useHarrisDetector=True

In [ ]:

```
plt.figure(figsize=(20,20))
plt.imshow(warp_imgs_all_gftt)
plt.title('Mosaic using Gftt Image')
```

In [ ]:

```
amax,amin,zmax,zmin,d,i,q,ht = warpnImages(images_left_bgr_no_enhance, images_right_bgr_no_enhance,H_left_freak,H_right_freak)
```

In [ ]:

```
warp_image_left = final_steps_left_union(images_left_bgr_no_enhance,H_left_freak,amax,amin,zmax,zmin,d,i,q,ht)
```

In [ ]:

```
warp_imgs_all_gftt = final_step_right_union(warp_image_left,images_right_bgr_no_enhance,H_right_freak,amax,amin,zmax,zmin,d,i,q,ht)
```

In [ ]:

```
plt.figure(figsize=(20,20))
plt.imshow(warp_imgs_all_gftt)
plt.title('Mosaic using FREAK image')
```

In [ ]:

```
amax,amin,zmax,zmin,d,i,q,ht = warpnImages(images_left_bgr_no_enhance, images_right_bgr_
no_enhance,H_left_fast,H_right_fast)
```

In [ ]:

```
warp_image_left = final_steps_left_union(images_left_bgr_no_enhance,H_left_fast,amax,amin
,zmax,zmin,d,i,q,ht)
```

In [ ]:

```
warp_imgs_all_agast = final_step_right_union(warp_image_left,images_right_bgr_no_enhance,
H_right_fast,amax,amin,zmax,zmin,d,i,q,ht)
```

In [ ]:

```
plt.figure(figsize=(20,20))
plt.imshow(warp_imgs_all_fast)
plt.title('Mosaic using FAST image')
```

In [ ]:

```
amax,amin,zmax,zmin,d,i,q,ht = warpnImages(images_left_bgr_no_enhance, images_right_bgr_
no_enhance,H_left_sift,H_right_sift)
```

In [ ]:

```
warp_image_left = final_steps_left_union(images_left_bgr_no_enhance,H_left_sift,amax,amin
,zmax,zmin,d,i,q,ht)
```

In [ ]:

```
warp_imgs_all_sift = final_step_right_union(warp_image_left,images_right_bgr_no_enhance,H
_right_sift,amax,amin,zmax,zmin,d,i,q,ht)
```

Using parameters in SIFT , contrastThreshold=0.08,edgeThreshold=10,sigma=1.8

In [ ]:

```
plt.figure(figsize=(20,20))
plt.imshow(warp_imgs_all_sift)
plt.title('Mosaic using SIFT image')
```

In [ ]:

```
amax,amin,zmax,zmin,d,i,q,ht = warpnImages(images_left_bgr_no_enhance, images_right_bgr_
no_enhance,H_left_kaze,H_right_kaze)
```

In [ ]:

```
warp_image_left = final_steps_left_union(images_left_bgr_no_enhance,H_left_kaze,amax,amin
,zmax,zmin,d,i,q,ht)
```

In [ ]:

```
warp_imgs_all_kaze = final_step_right_union(warp_image_left,images_right_bgr_no_enhance,H
_right_kaze,amax,amin,zmax,zmin,d,i,q,ht)
```

In [ ]:

```
plt.figure(figsize=(20,20))
plt.imshow(warp_imgs_all_kaze)
plt.title('Mosaic using KAZE Image')
```

In [ ]: